



US010258739B2

(12) **United States Patent**
Cefai

(10) **Patent No.:** **US 10,258,739 B2**
(45) **Date of Patent:** **Apr. 16, 2019**

(54) **MECHANICAL DRIVER**

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(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 141 days.

(21) Appl. No.: **15/359,914**

(22) Filed: **Nov. 23, 2016**

(65) **Prior Publication Data**

US 2017/0072137 A1 Mar. 16, 2017

Related U.S. Application Data

(62) Division of application No. 14/388,661, filed as application No. PCT/NL2013/050227 on Mar. 27, 2013, now Pat. No. 9,987,418.

(30) **Foreign Application Priority Data**

Mar. 28, 2012 (GB) 1205459.9

(51) **Int. Cl.**
F03G 7/06 (2006.01)
F04B 9/02 (2006.01)

(Continued)

(52) **U.S. Cl.**
CPC **A61M 5/1452** (2013.01); **A61M 5/1454** (2013.01); **F03G 7/065** (2013.01);
(Continued)

(58) **Field of Classification Search**
CPC . A61M 5/1452; A61M 5/1454; F04B 19/006;
F04B 43/043; F04B 9/02; F03G 7/06
See application file for complete search history.

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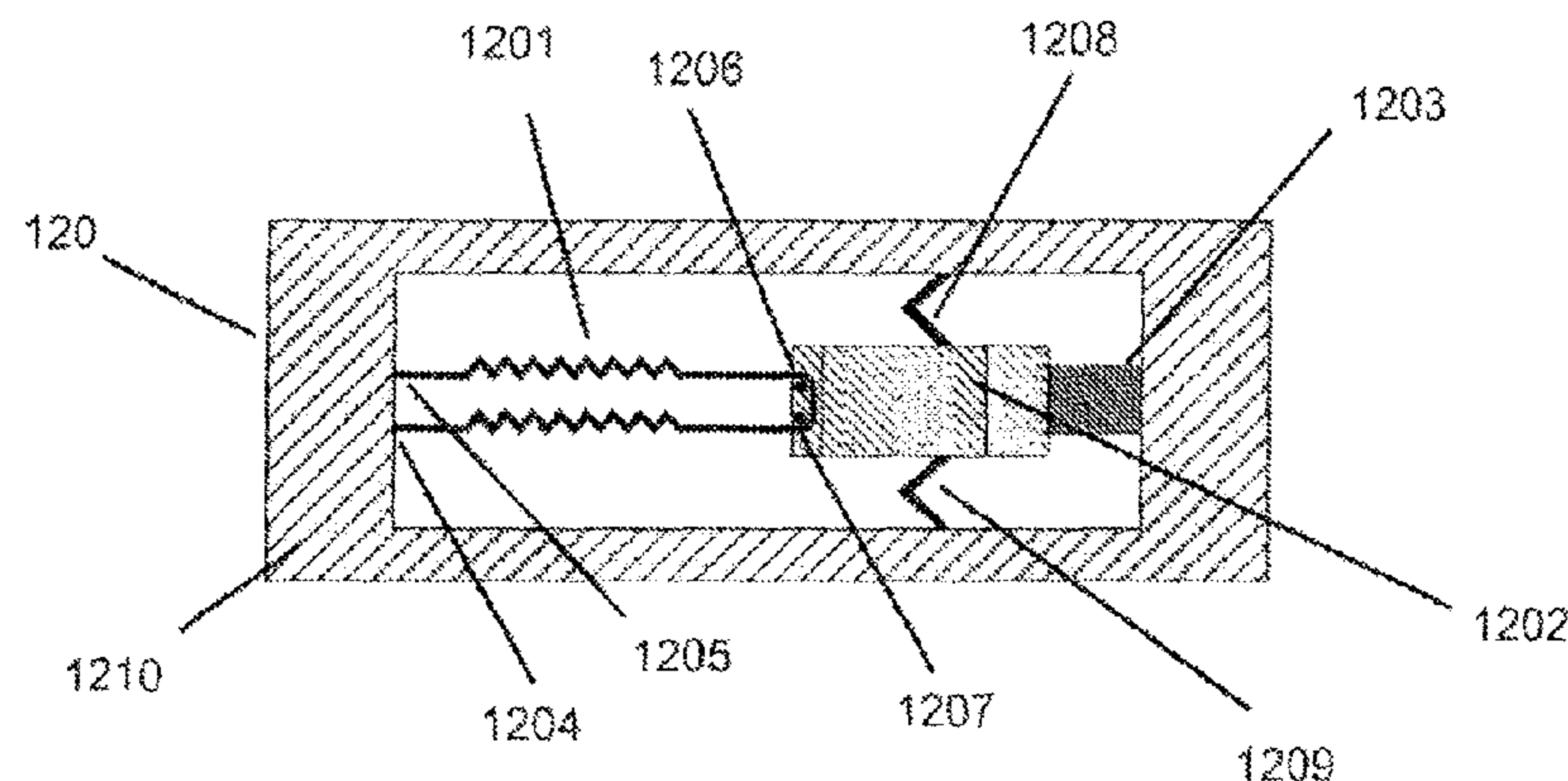
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(57) **ABSTRACT**

A mechanical driver comprising a wedge shaped member operatively coupled to a shape memory alloy such that the shape memory alloy is able to displace the wedge shaped member in an essentially linear direction. The wedge shaped member is in constant contact with a lever arranged so that it can rotate about a fixed pivot point. A piston is arranged such that it is constant contact with the lever at a point between the pivot point of the lever and the contact point between the lever and the wedge shaped member. Activation of the shape memory alloy displaces the wedge shaped member along its linear direction and this causes the lever to be deflected about its pivot point and the piston to be deflected in an essentially linear direction that is perpendicular to the linear direction of travel of the wedge shaped member.

22 Claims, 10 Drawing Sheets



(51) Int. Cl.

A61M 5/145 (2006.01)
F04B 19/00 (2006.01)
F04B 43/04 (2006.01)
F04B 17/00 (2006.01)

(52) U.S. Cl.

CPC F04B 9/02 (2013.01); F04B 17/00
(2013.01); F04B 19/006 (2013.01); F04B
43/043 (2013.01); A61M 2005/14506
(2013.01); A61M 2205/0244 (2013.01); A61M
2205/0266 (2013.01); A61M 2207/00
(2013.01)

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Fig. 1.

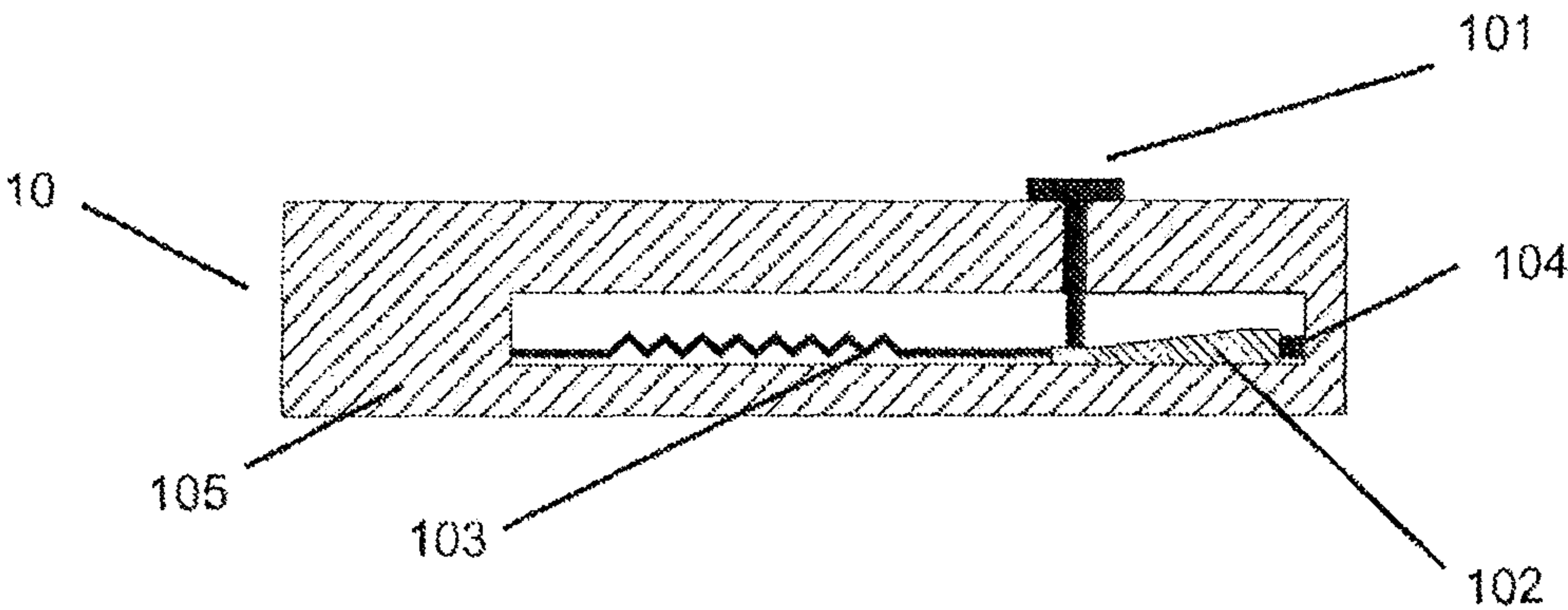


Fig. 2.

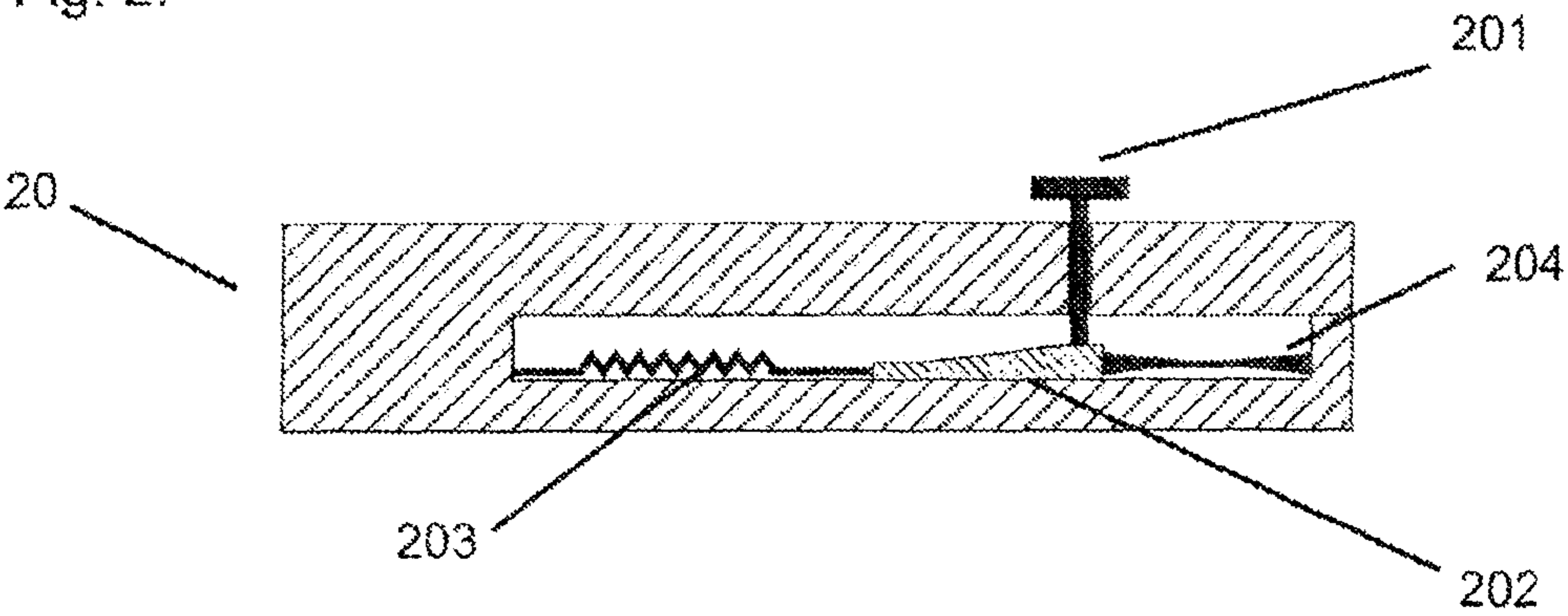


Fig. 3.

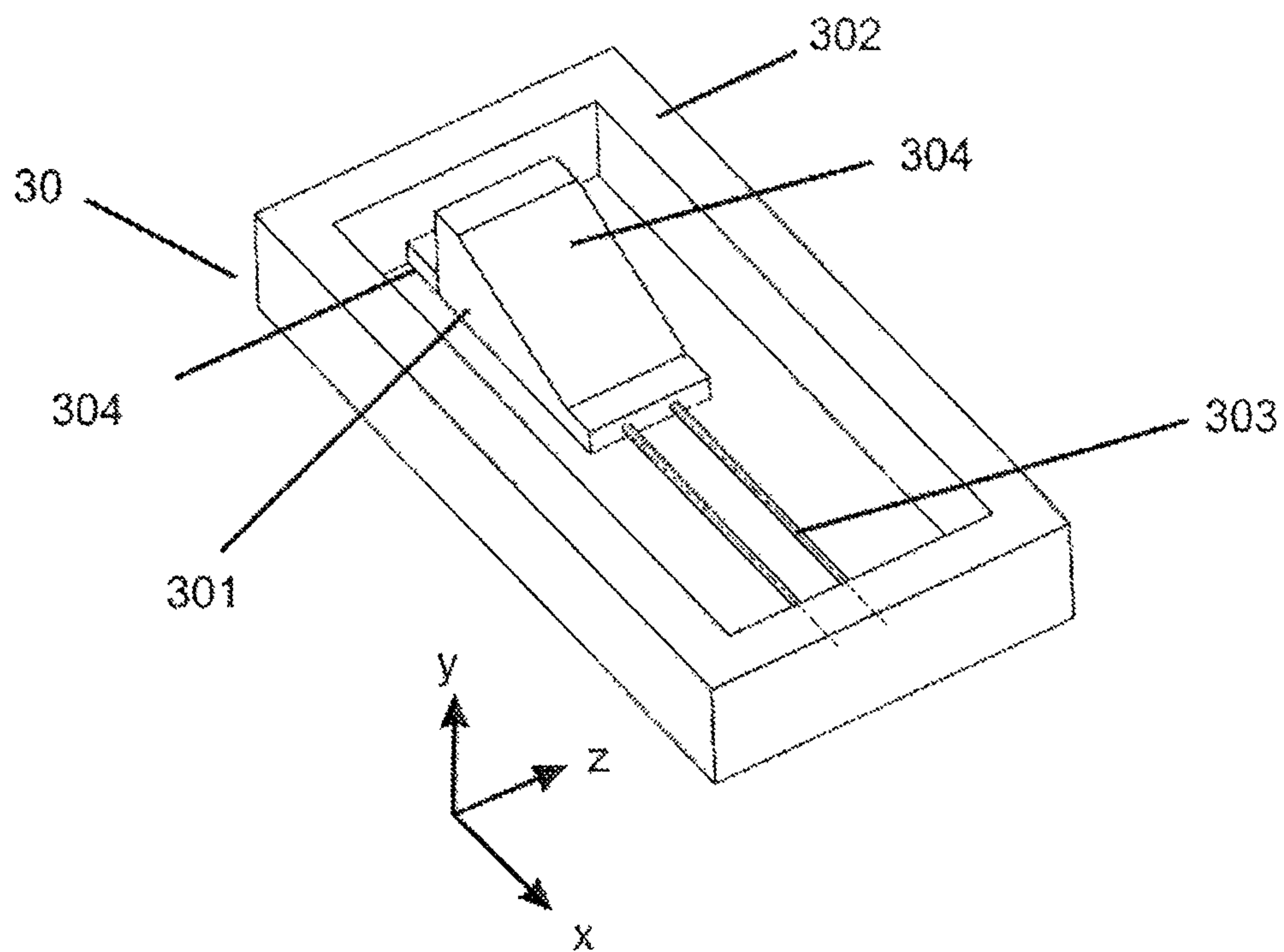


Fig. 4.

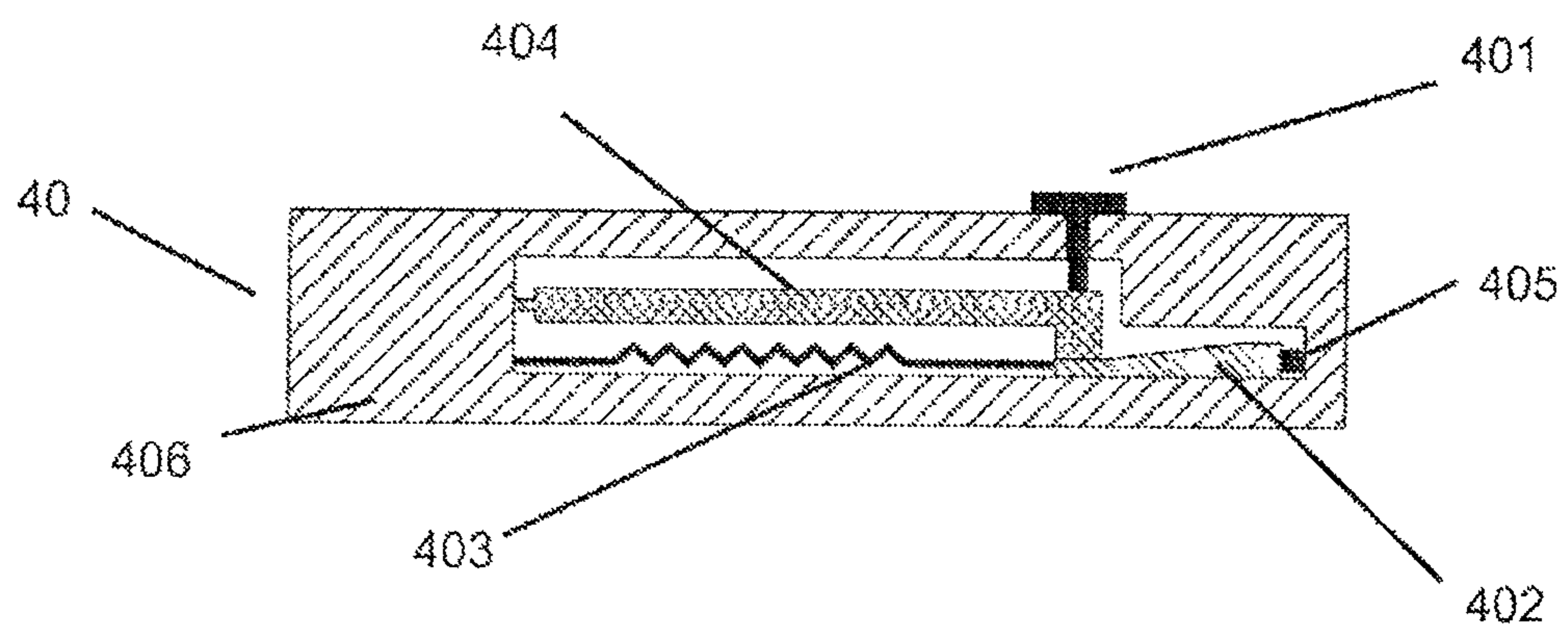


Fig. 5.

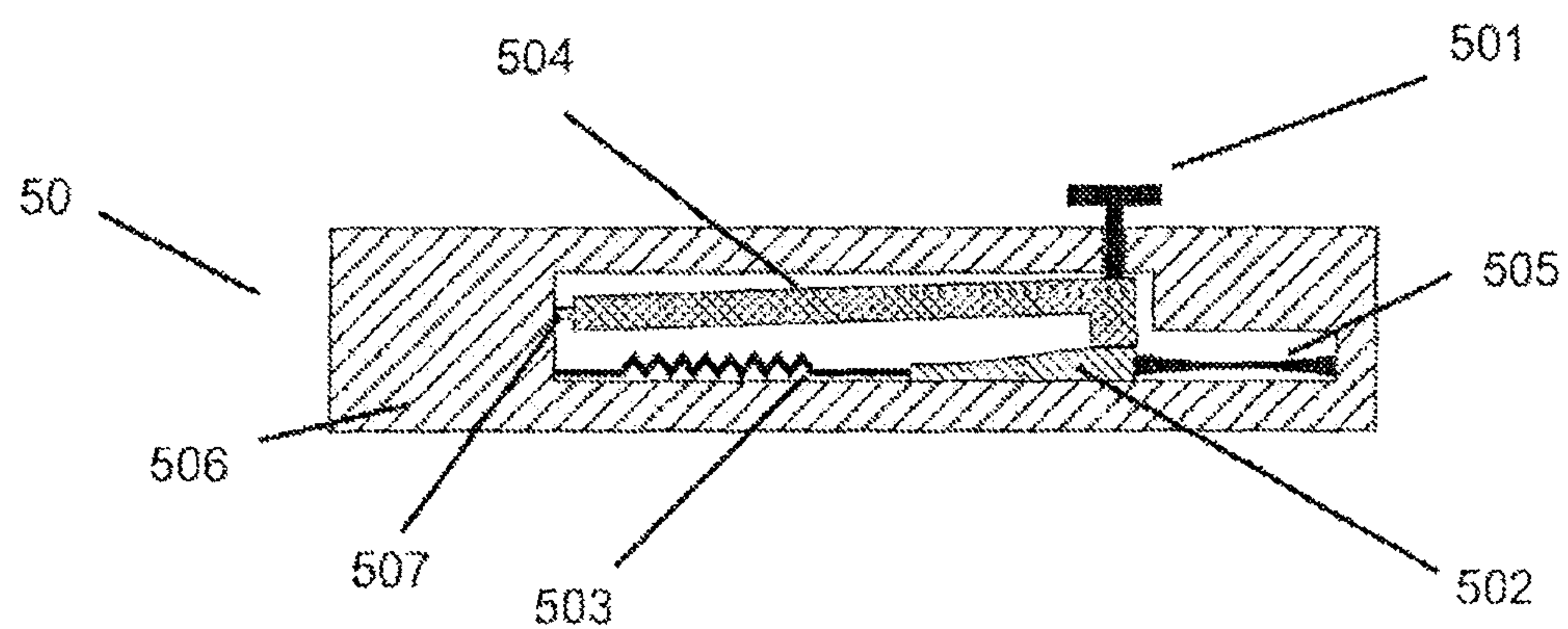


Fig. 6.

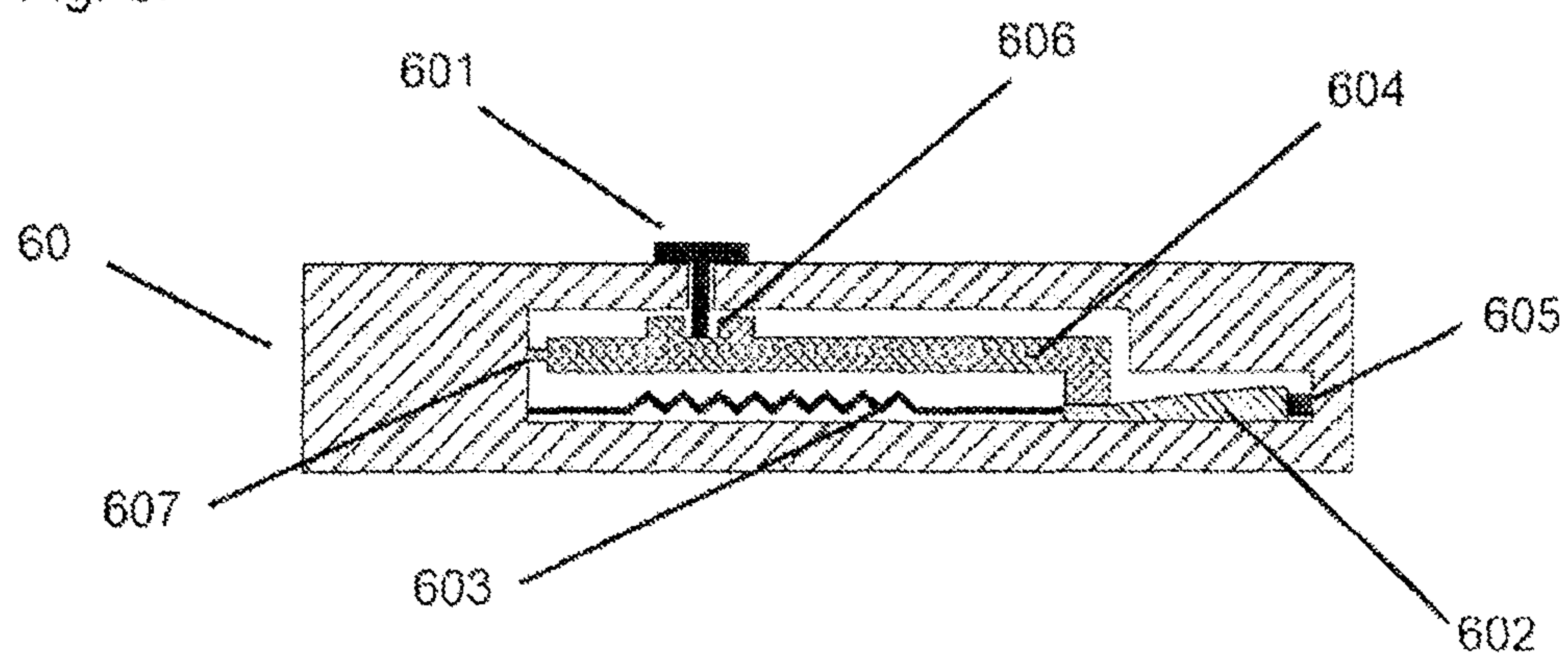


Fig. 7.

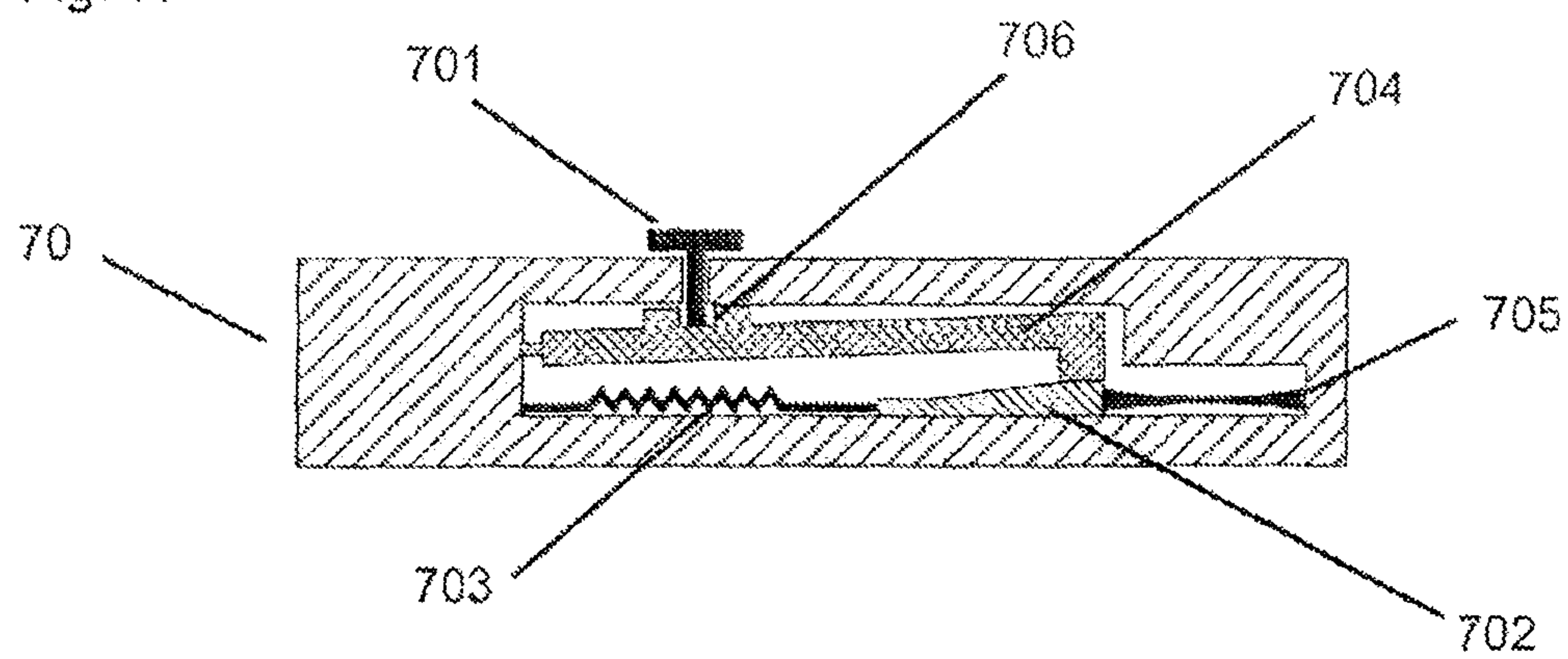


Fig. 8.

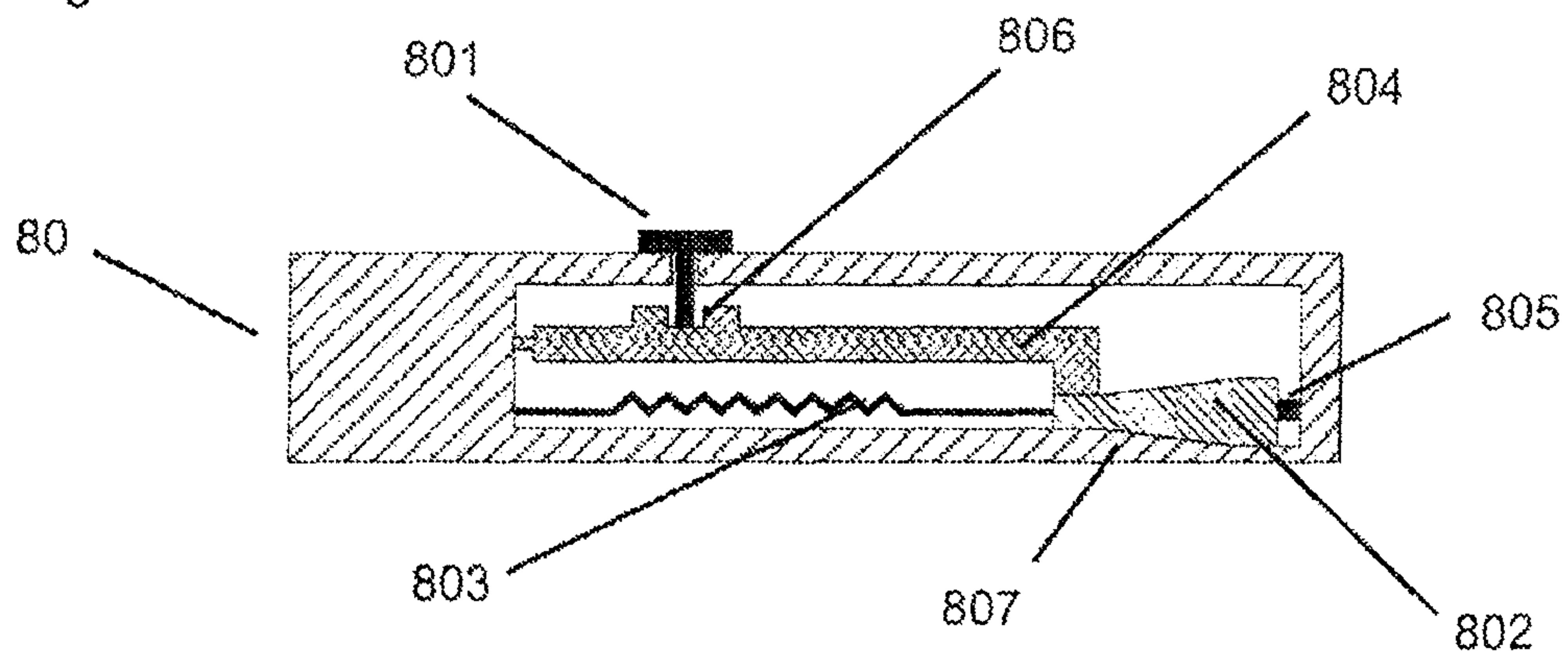


Fig. 9.

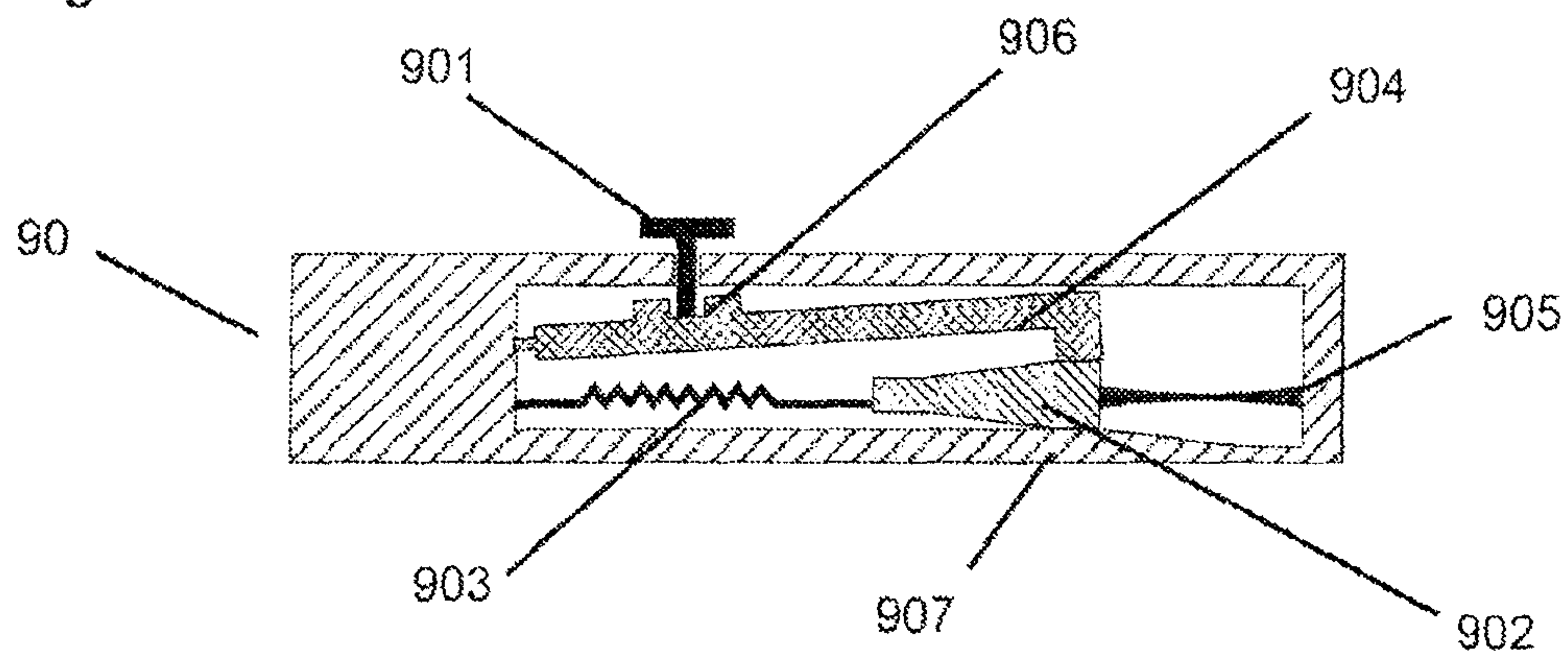


Fig. 10.

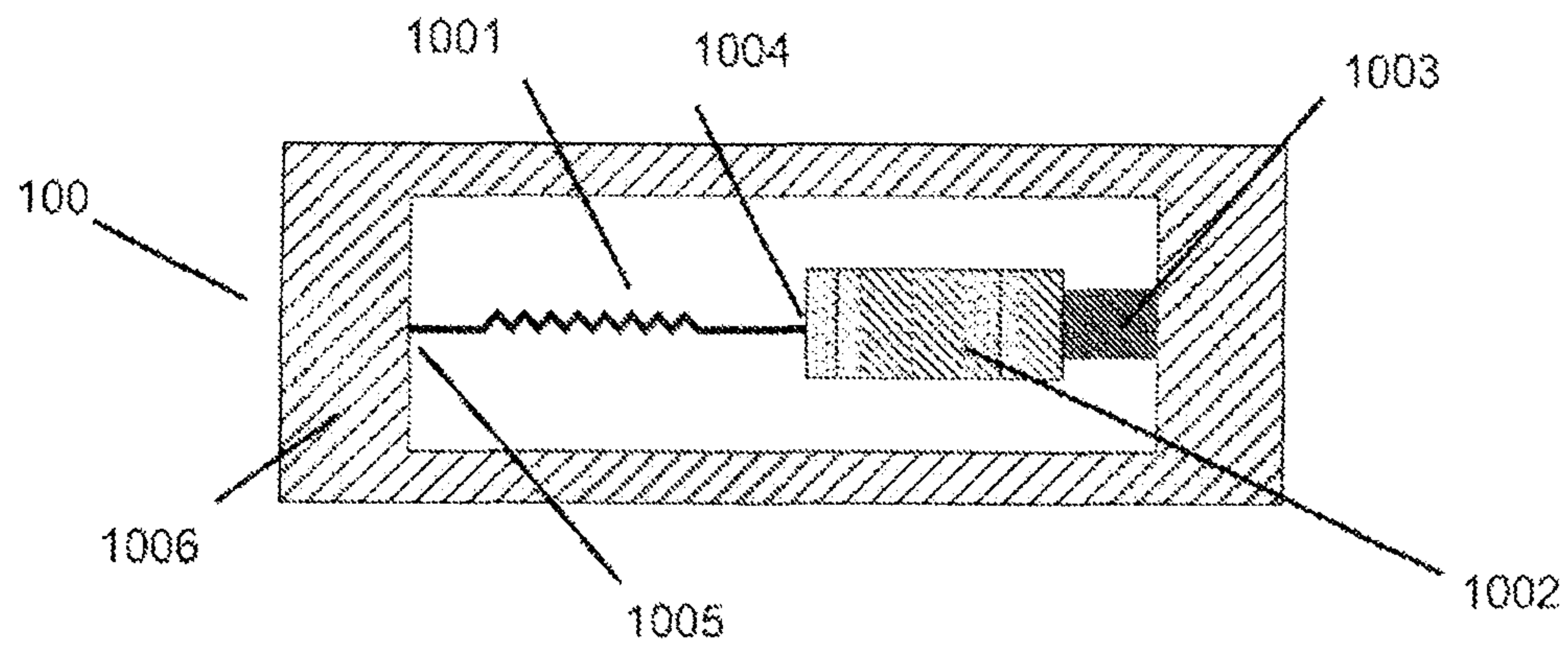


Fig. 11.

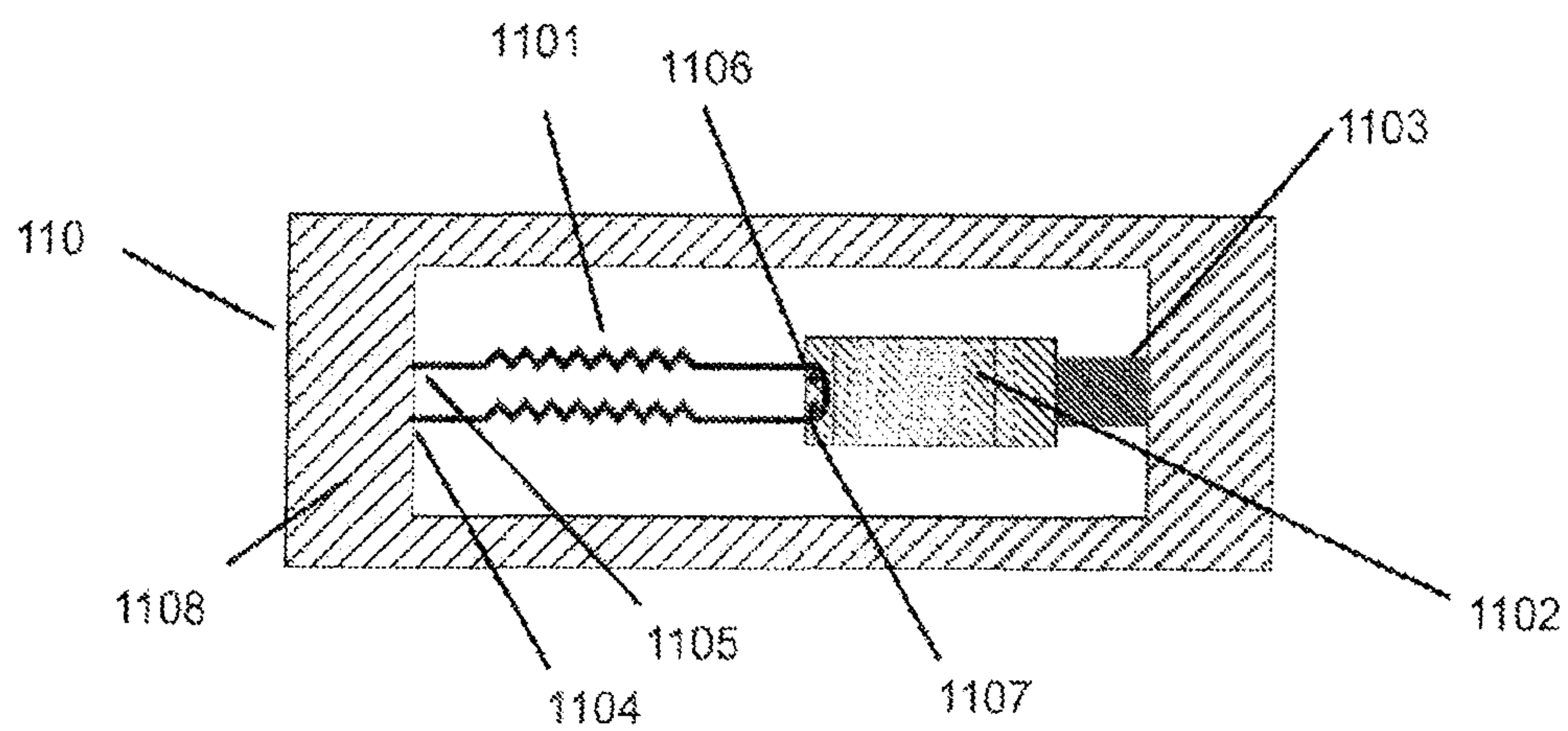


Fig. 12

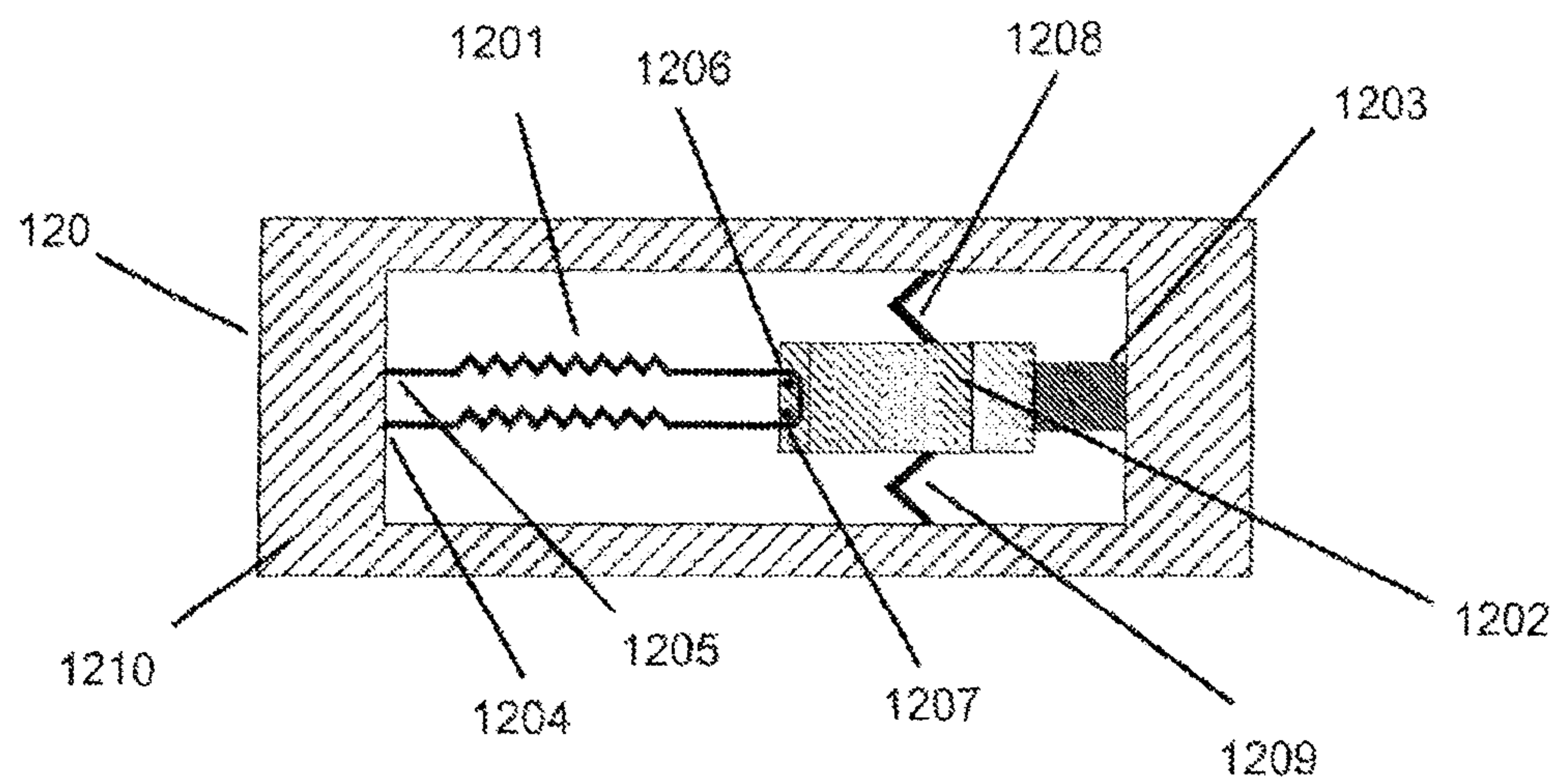


Fig. 13.

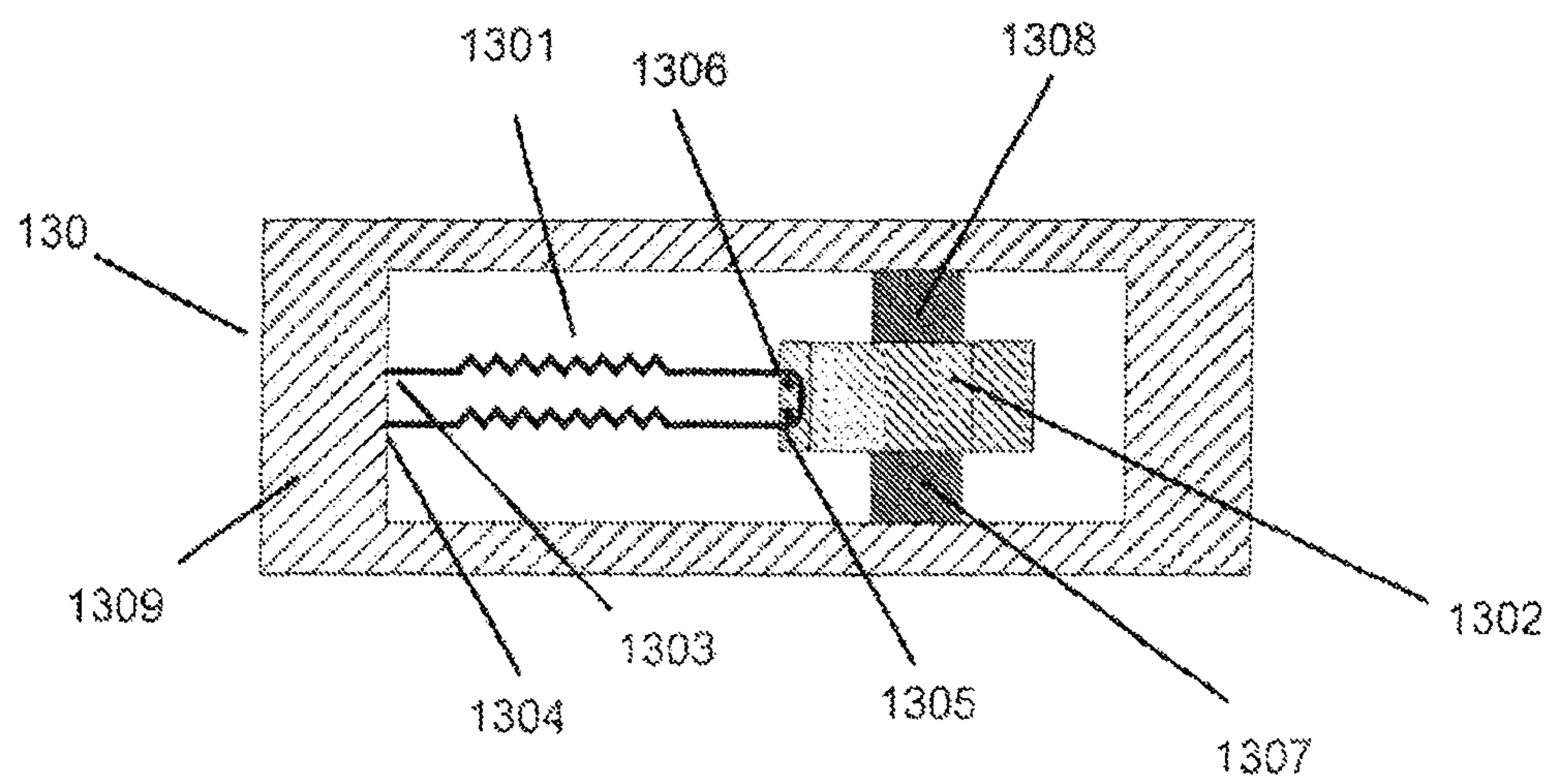


Fig. 14.

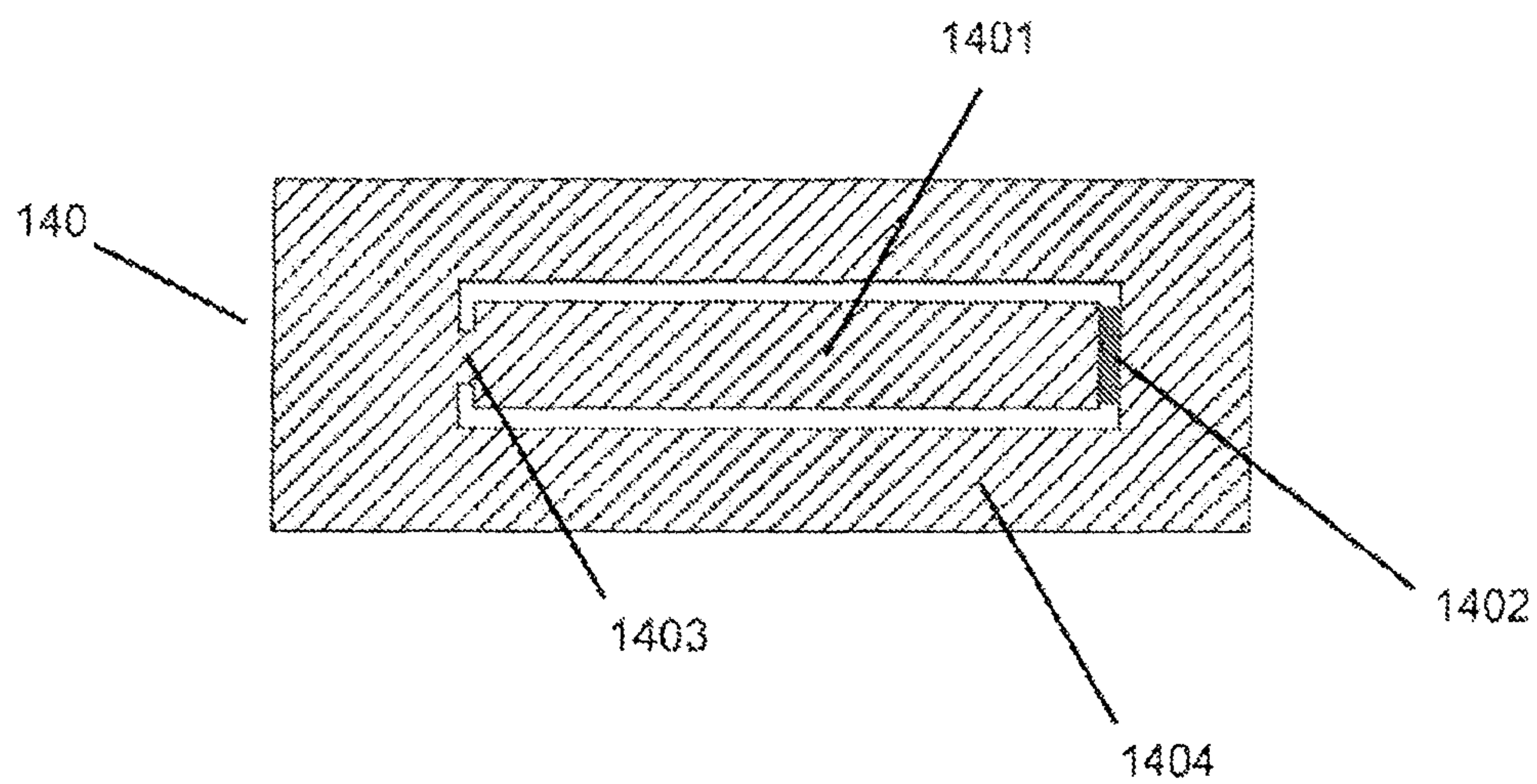


Fig. 15.

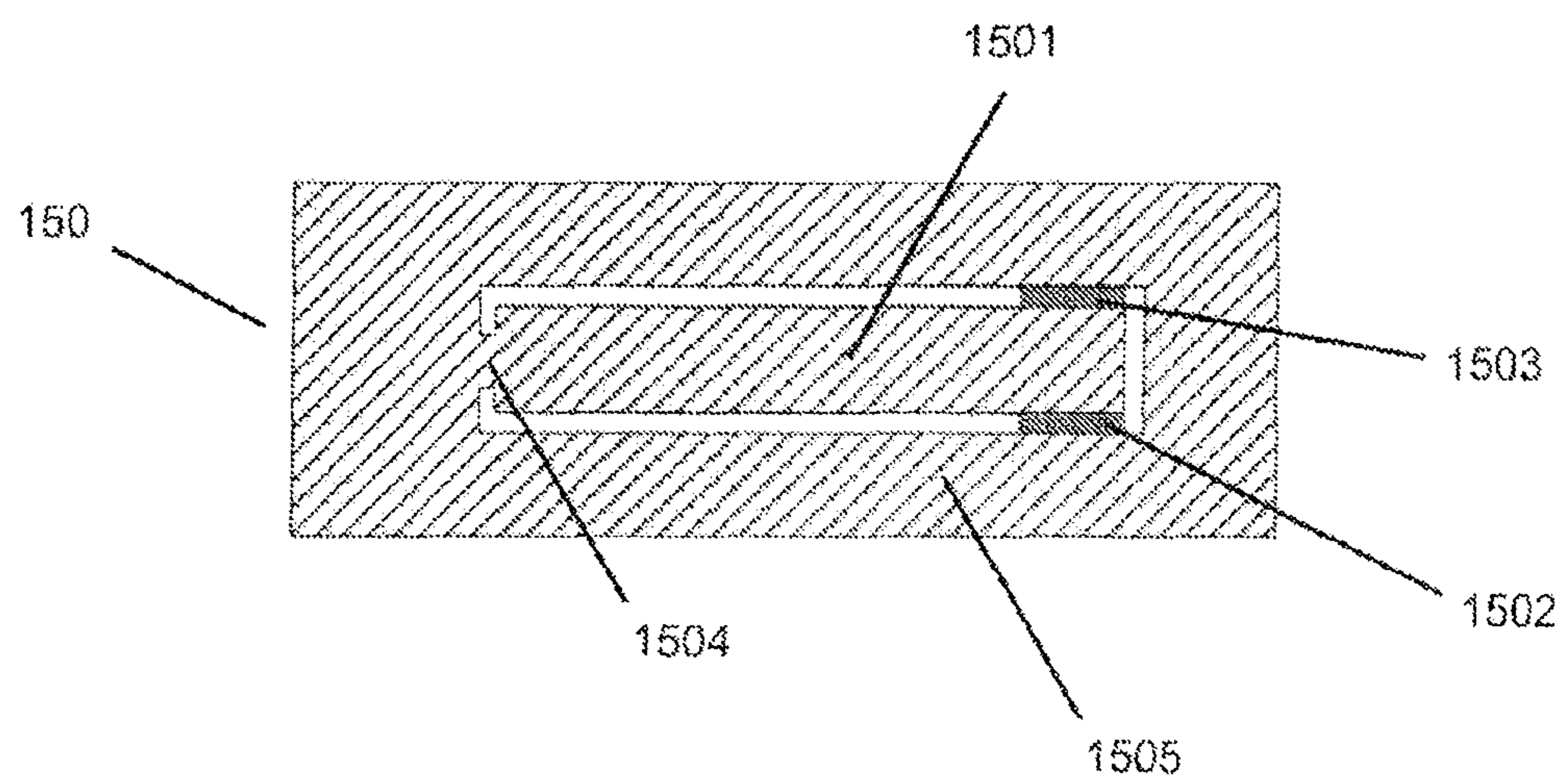


Fig. 16.

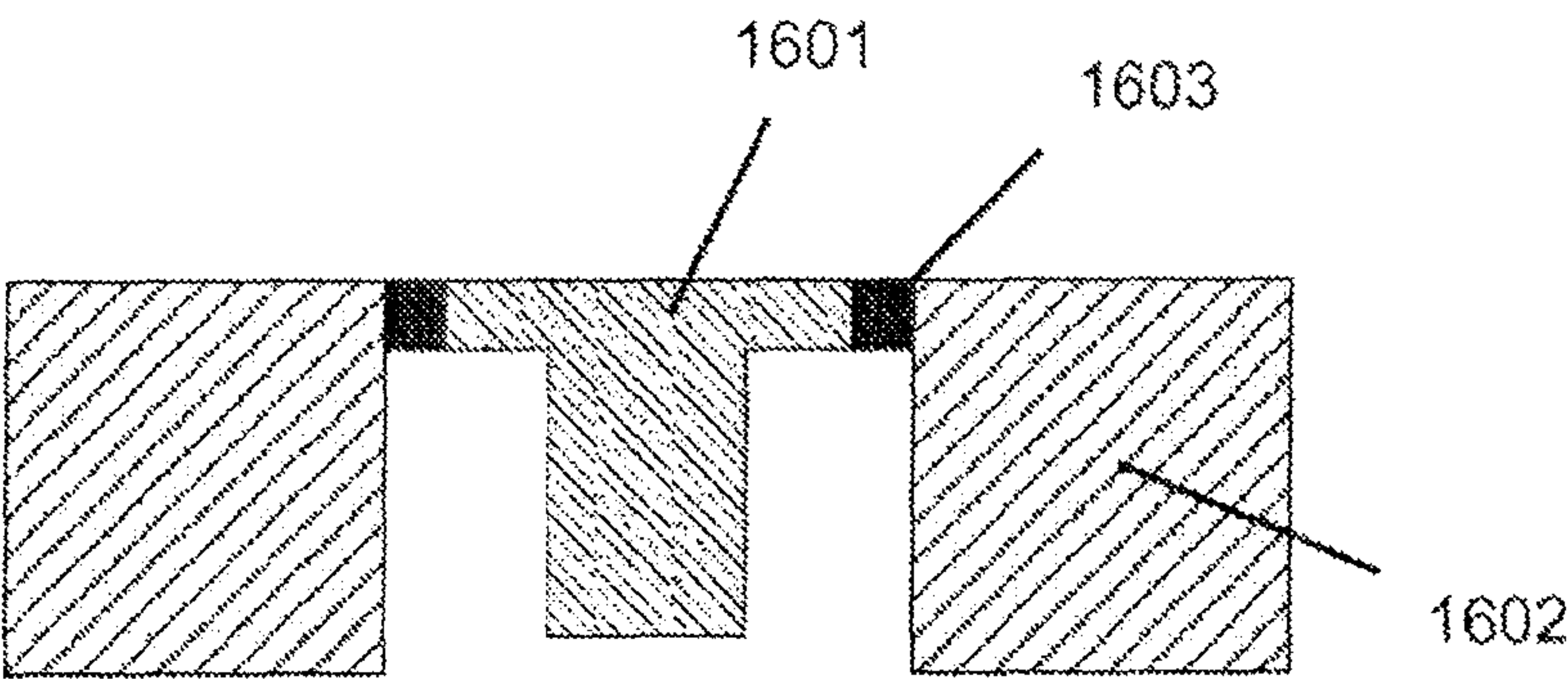


Fig. 17.

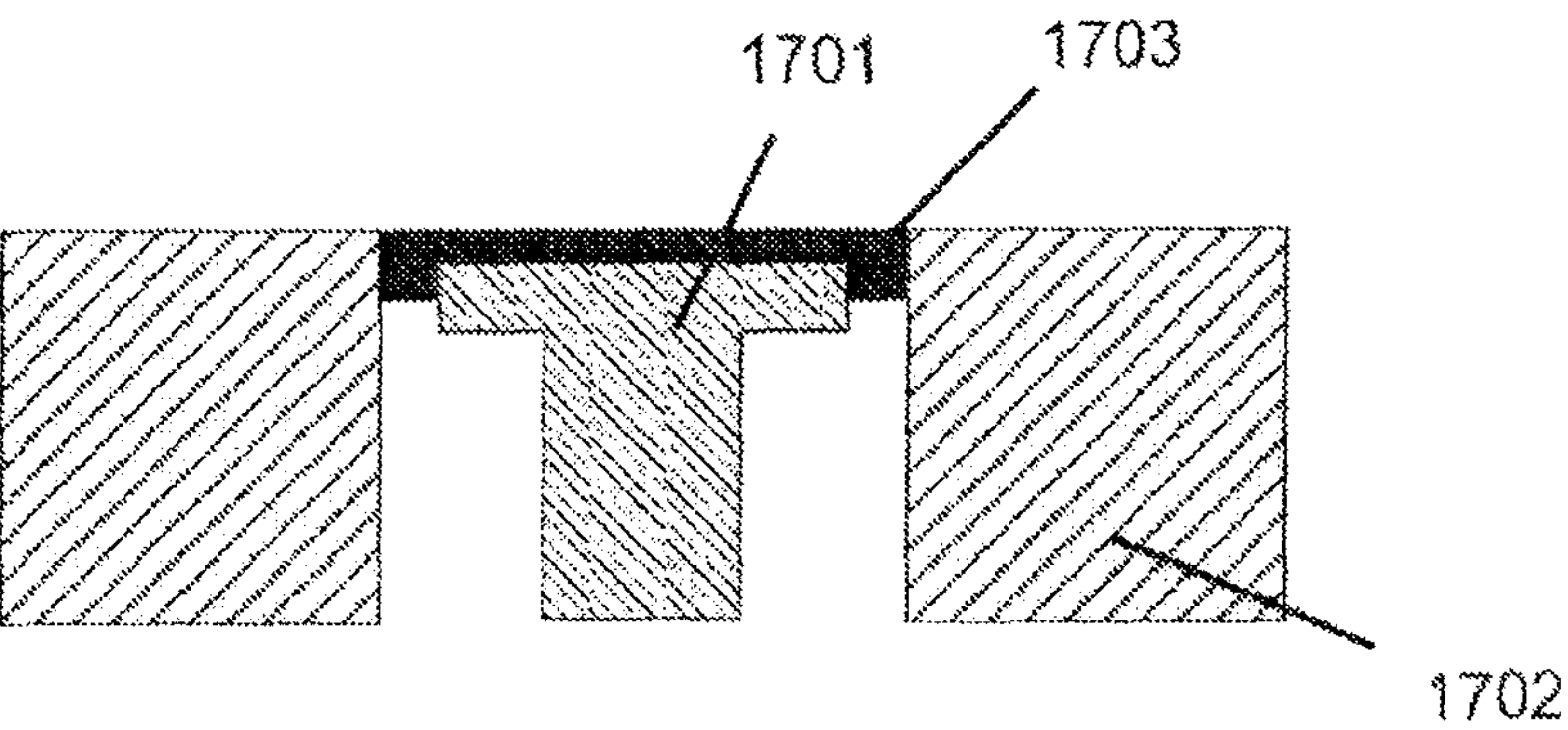


Fig. 18.

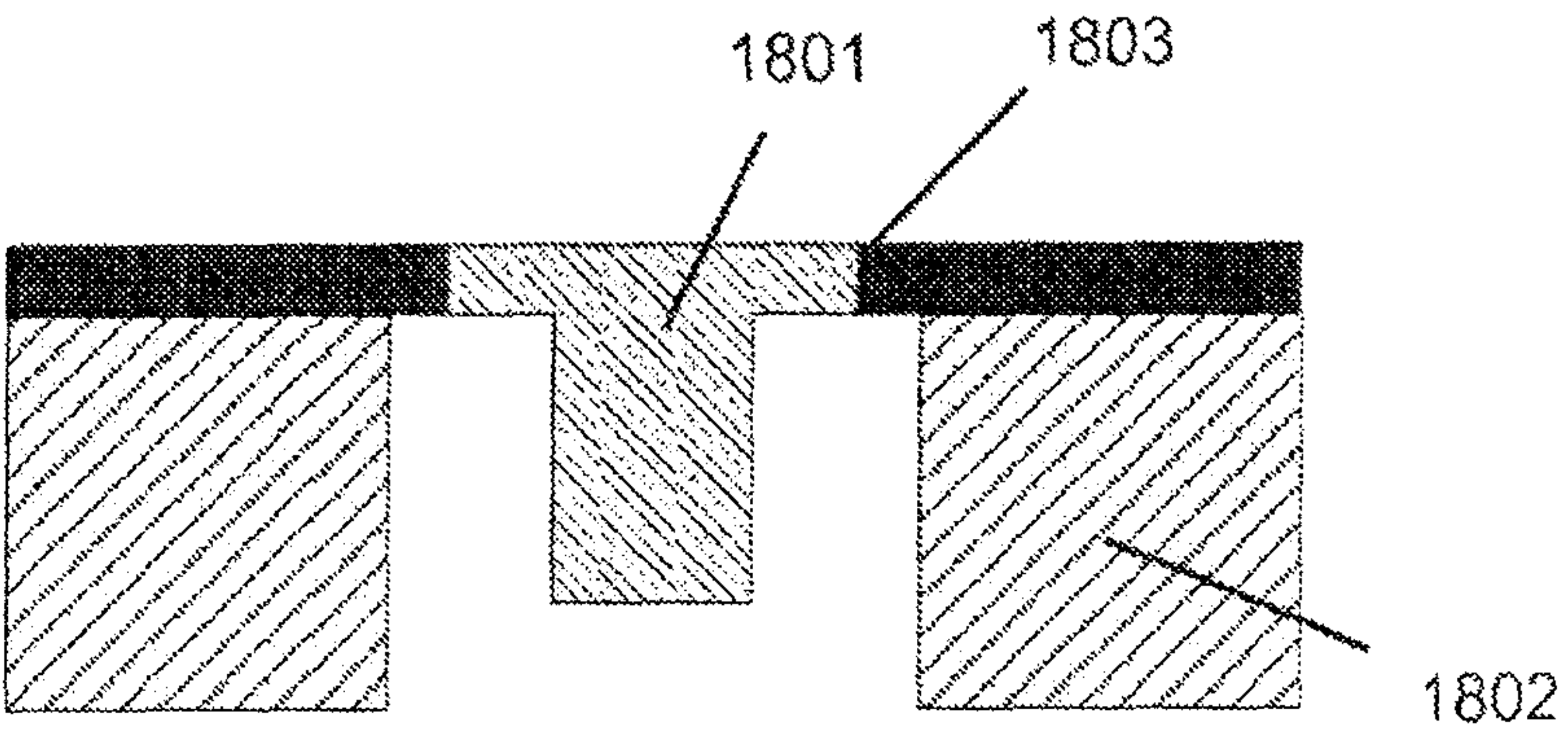


Fig. 19.

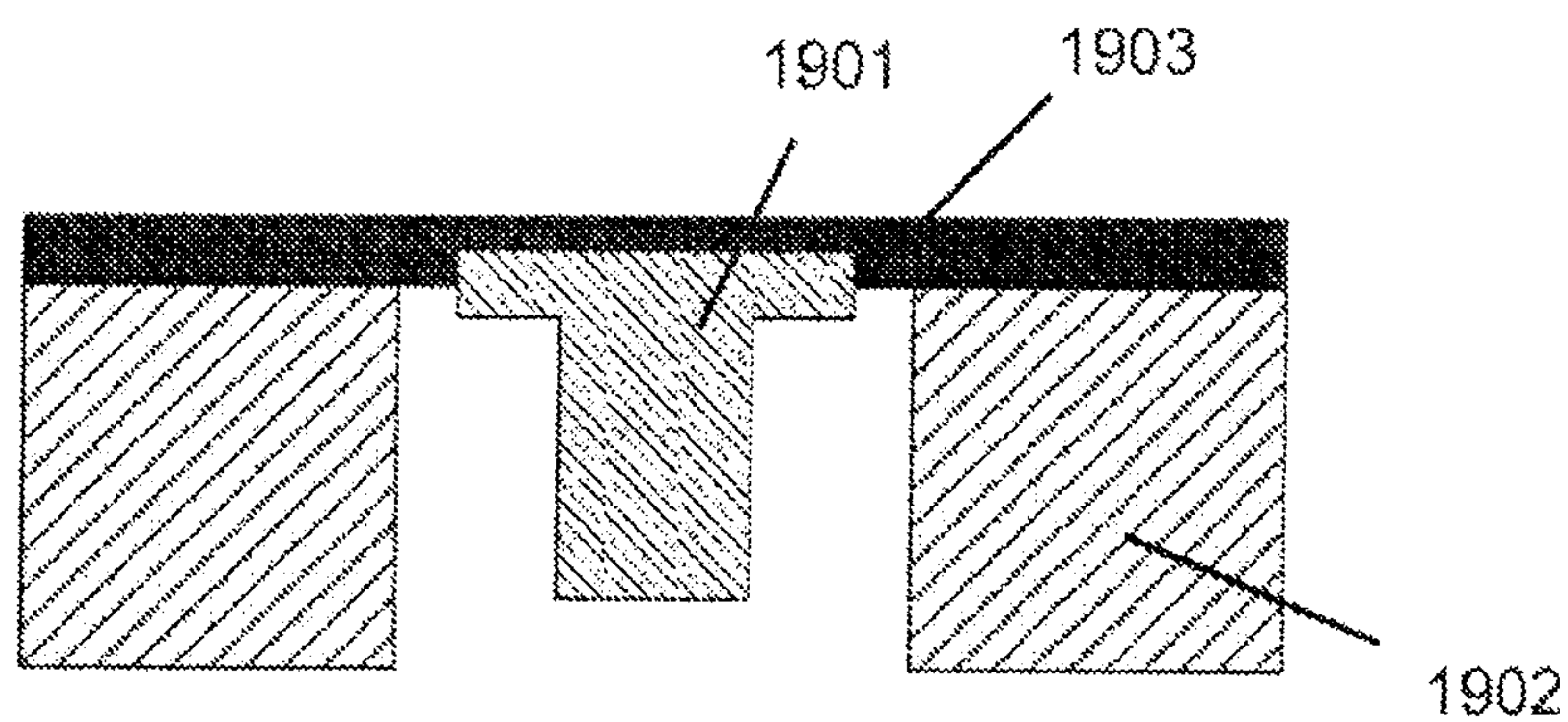


Fig. 20.

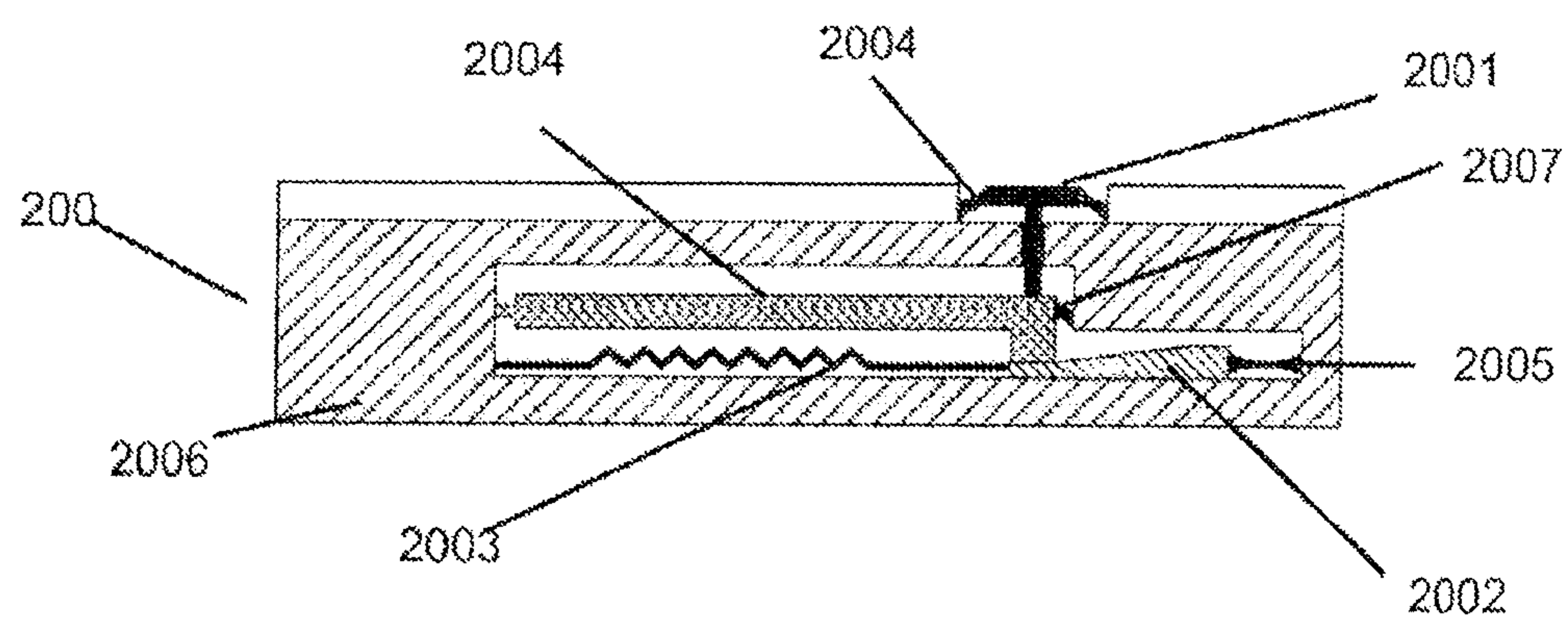


Fig. 21.

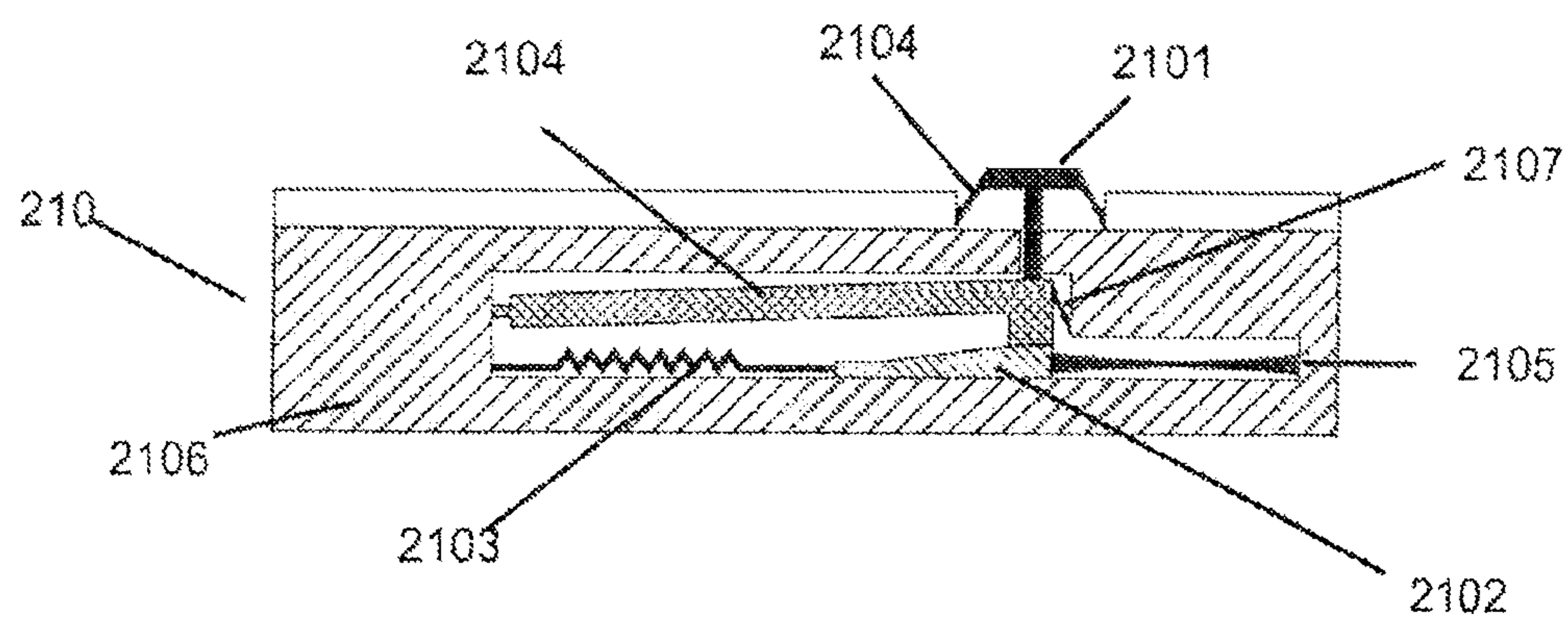
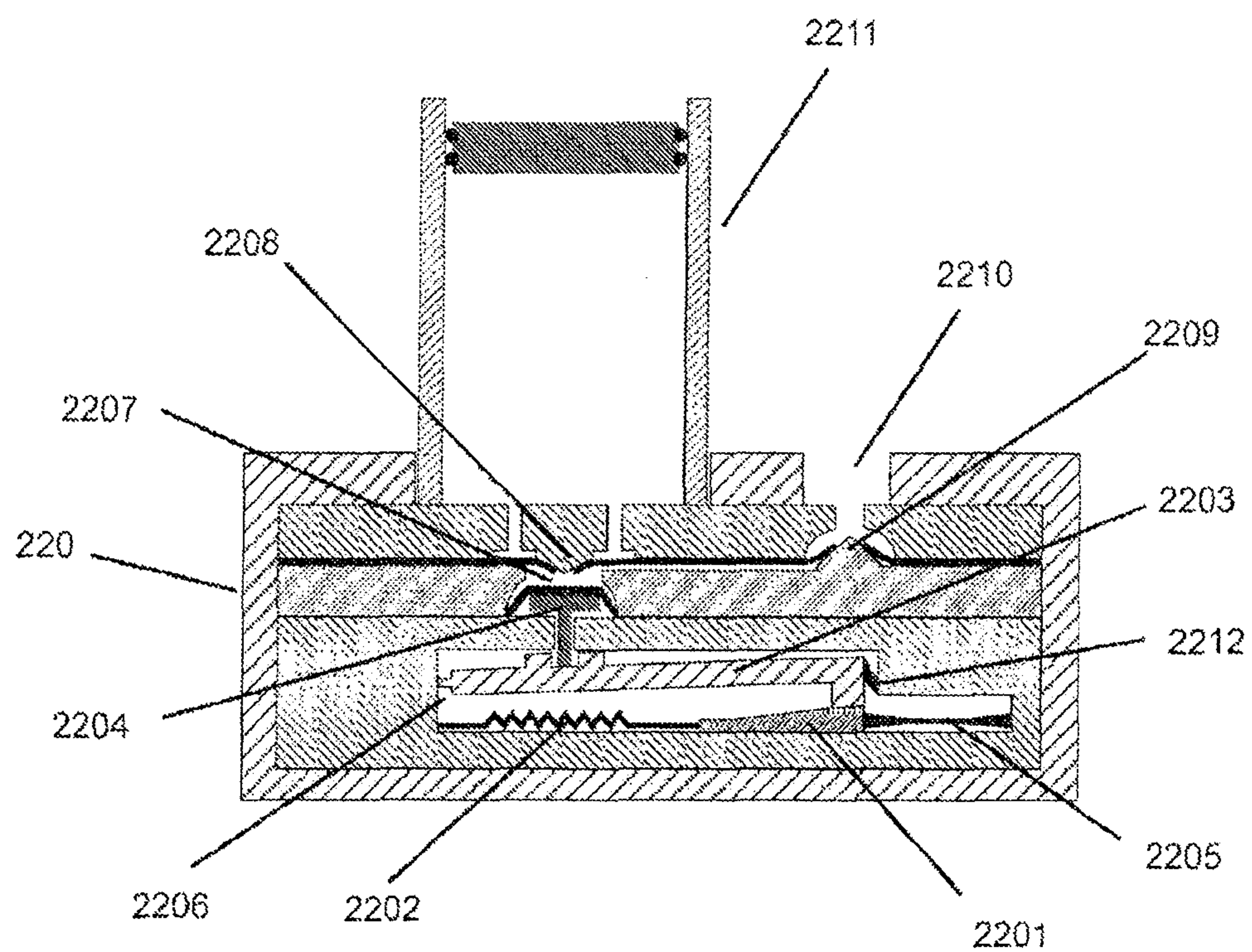


Fig. 22.



MECHANICAL DRIVER

The present application is a divisional of U.S. Ser. No. 14/388,661, which is a § 371 submission of international application no. PCT/NL2013/050227, filed 27 Mar. 2013 and published in the English language on 3 Oct. 2013 with publication no. WO 2013/147602, which claims the benefit of the filing date of GB 1205459.9 filed 28 Mar. 2012.

BACKGROUND

This invention relates to a mechanical driver. Said mechanical driver can be miniature mechanical driver and is often used in a micro-pump. The micro-pump can be used as the fluid pumping device of a drug delivery system.

A variety of mechanical drivers have been described for providing the mechanical displacement required in devices designed for pumping fluids. Examples of these mechanical drivers include devices operating on thermo-pneumatic (U.S. Pat. Nos. 4,265,600 and 6,520,753), electrostatic (U.S. Pat. Nos. 6,168,395 and 5,362,213), piezo electric (U.S. Pat. Nos. 4,596,575 and 6,827,559), thermo-hydraulic (GB2443261), bimetallic (U.S. Pat. No. 5,611,676), stepper motors (EP2072072) and magnetic (U.S. Pat. Nos. 3,819, 305 and 7,922,462) mechanical driving principles.

A number of limitations exist with these mechanical driving principles when incorporated into micro-pump designs. A number of these mechanical drivers are too complex and lead to difficulties when designing a product where large numbers need to be manufactured, that are manufactured at high throughput and where the manufacturing process is required to deliver product at a cost effective price. The complexity also limits the design opportunities when they are incorporated into micro-pumps. Other limitations are that the components required in some of the mechanical drivers described above result in a product that is too costly or difficult to manufacture. Yet another limitation is that the materials required when incorporating at least some of the mechanical drivers mentioned above into micro-pump products reduce the opportunities for using the product. As an example, some materials are not compatible with the fluid media that the product is required to pump, because it degrades the commercially important components in the media. This could include commercially important components such as bioactive materials. Yet in other instances, some of the mechanical driving principles are not able to provide the accuracy required for micro-pumps required for drug delivery and other commercially important components. And yet another limitation is that some of the above mechanical driving principles are not able to provide the repeatability required by certain drug delivery products. By way of example, products designed for short term use and that are replaced on a frequent basis require driving principles that can provide repeatable performance across a large number of similar devices. And yet another limitation is that some of the above mechanical driving principles do not provide the power required by the drug delivery device when the mechanical driver is miniaturised.

Shape memory alloy (SMA) has been proposed as a suitable material for a mechanical driver of the type described above and a number of devices based on this mechanical driver have been described. SMA mechanical drivers can be suitable for micro-pump applications due to their high force-to-weight ratio, mechanical simplicity, compactness, and silent, clean operation. SMA mechanical drivers also provide cost effective solutions for the design of

short term use, disposable products that are easy to manufacture, that are produced in very large numbers and at a cost effective price.

However, SMA mechanical drivers have disadvantages that limit their use in applications that require high accuracy.

One disadvantage of using SMA in these devices is that it has a prominent strain hysteresis and its phase transition is dependent on temperature, stress, the direction of motion, and many other factors (J. D. Harrison, "Measurable Change Concomitant with SME Transformation," *Engineering Aspects of SMAs*, eds. Duering et al., Butterworth, pp 106-209, 1990).

Nonlinear control approaches have been used to compensate for the non-mechanical non-linearity of shape memory alloys. These approaches have included various approaches to controlling the mechanical movement of shape memory alloys such as: neural networks and a sliding mode based robust controller (Song, "Precision tracking control of shape memory alloy actuators using neural networks and a sliding-mode based robust controller," *Smart Mater. Struct.* 12, pp. 223-231, 2003), neural fuzzy (Kumagai, "Neuro-fuzzy model based feedback controller for shape memory alloy actuators," *Proceedings of SPIE*, v 3984, pp. 291-9, 2000) dissipativity (Gorbet, "Dissipativity approach to stability of a shape memory alloy position control system," *IEEE Transactions on Control Systems Technology*, v 6, n 4, pp. 554-562, July 1998), variable structure control (Grant, "Variable structure control of shape memory alloy actuators," *IEEE Control Systems Magazine*, v 17, n 3, pp. 80-88, June 1997), and pulse width modulation of the actuation energy (NMa and G Song, "Control of shape memory alloy actuator using pulse width modulation," *Smart Mater. Struct.* 12, pp. 712-719, 2003). Despite these often complex approaches to shape memory alloy control, the control of SMA is still difficult.

Several approaches have also been proposed to generate the accuracy of movement required from SMA mechanical drivers by mechanically limiting the range of movement that the SMA can perform. EP2290238A1 describes a device that limits the range of movement of a plunger in a fluid delivery device by providing mechanical stops for both the start and end of the plunger travel. U.S. Pat. No. 7,232,423 describes a device that also uses mechanical stops to accurately define the range of movement created by the SMA mechanical driver. A limitation of these inventions is that these mechanical stops impart strain on the SMA and limit the performance of the driver and could also lead to failure. U.S. Pat. No. 8,047,812 describes a device that aims to reduce the effect of unwanted strain on the SMA by introducing a second piston coupled to the shape memory element that moves to accommodate changes in the shape memory element and reduce stress on the pumping system. By introducing the second piston, this invention increases the complexity of the device, making it more difficult to manufacture and less cost effective. U.S. Pat. No. 8,029,245 describes a device that relies on monitoring the position of the piston in the pumping system and then modulating the energy supplied to the SMA to provide the accuracy required. The requirement for monitoring the position of the plunger in this invention introduces the need for complex sensor and control systems that complicate the design and operation of the device. These added complications also increase the cost and complexity of manufacturing the device. U.S. Pat. No. 6,656,158 describes a fluid dispensing device that uses a SMA to move a pawl against a toothed gear system attached to the fluid dispensing portion of the device. Every time the SMA is activated the pawl moves against the gear and indexes the

gear from its first position to a second position. The gear does not return to its first position. This device overcomes the lack of accuracy in the use of SMA, by using the SMA to move an accurately formed gear system. U.S. Pat. No. 6,375,638 describes a device that is similar to the one described in U.S. Pat. No. 6,656,158. U.S. Pat. No. 6,375,638 describes a device where the SMA is used to move a part that then deflects a second part from its first position to a second position. The part that is moved can either move in a linear motion or an angular motion. It is important to note, that this part does not return to its first position, but indexes along the path of travel every time the SMA is activated. In both U.S. Pat. Nos. 6,656,158 and 6,375,638, the complexity of the device described increases the complexity of the manufacturing process and the cost-effectiveness of the manufactured device.

There is a need for an improved shape memory actuator mechanical driver that provides the required accuracy, reliability, ease of manufacture, cost effectiveness and that is scalable and that can be used to drive the reciprocating piston in a micro pump. These will become apparent in the description of the present invention.

STATEMENT OF INVENTION

The invention relates to a mechanical driver comprising a lever which is rotatable at a fixed rotation point, a wedge shaped member operatively coupled to and in constant contact with the lever at a point at a distance from the fixed rotation point to deflect the lever about the fixed rotation point, a shape memory alloy operatively coupled to the wedge shaped member to move the wedge shaped member such that the wedge shaped member deflects the lever, wherein the shape memory alloy is held at a predetermined tension in its start position, and a piston drive point located on and in constant contact with the lever, at a distance from the fixed rotation point of the lever. Further embodiments of said mechanical driver are defined in the claims **2-27**. The mechanical driver can be a miniature mechanical driver.

The invention further relates to a mechanical driver comprising a piston, a wedge shaped member operatively coupled and in constant contact with the piston to deflect the piston, and a shape memory alloy operatively coupled to the wedge shaped member to move the wedge shaped member such that the wedge shaped member deflects the piston, wherein the shape memory alloy is held at a predetermined tension in its start position. Further embodiments of said mechanical driver are defined in the claims **29-46**. The mechanical driver can be a miniature mechanical driver.

In a further embodiment of any of the above mechanical drivers according to the invention, the shape memory alloy is arranged to move the wedge shaped member in a linear direction from a first position into a second position.

In a further embodiment of any of the above mechanical drivers according to the invention, the piston and the wedge shaped member are arranged so that when the wedge shaped member moves from its first position to its second position, the piston is displaced along a linear direction from a first position to a second position.

In a further embodiment of any of the above mechanical drivers according to the invention, the direction of the movement of the piston is perpendicular to the direction of the movement of the wedge shaped member. The design of the mechanical driver allows to accurately move a piston in a micro pump.

In a further embodiment of any of the above mechanical drivers according to the invention, the wedge shaped mem-

ber has an angled surface that is in contact with the piston and that acts to displace the piston when the wedge shaped member moves along its linear direction. The angled surface of the wedge shaped member forms an angle with the linear direction of travel of the wedge shaped member. The angle can be optimised to optimise the displacement of the piston. It will be apparent to those skilled in the art that the angle of the surface and the distance the wedge shaped member moves along its linear direction define the distance the piston is displaced from its first position to its second position. The angle that the angled surface of the wedge shaped member makes with the linear direction of travel of the wedge shaped member and the length of the angled surface can both be defined by the physical dimensions of the wedge shaped member. The advantage of this embodiment of the present invention is that the shape of the wedge shaped member determines the extent and accuracy of displacement of the piston. The angled surface of the wedge shaped member can be further modified to incorporate surfaces that are essentially planar to the direction of travel of the wedge shaped member. One surface can be added to the leading edge of the wedge shaped member and directly preceding the angled surface. The other planar surface can be added directly after the angled surface. The two planar surfaces and the sloping surface can be arranged so that they form a continuous surface. The wedge shaped member can be arranged so that when it is in its first position one end of the piston is in contact with the first planar surface. When the wedge shaped member is displaced along its linear direction of travel the end of the piston travels along the angled surface and is displaced from its first position to its second position. The extent to which the piston is displaced can be defined by the angle of the angled surface and the length of the angled surface. Once the piston reaches the second planar surface at the end of the angled surface it cannot be displaced further. The advantage of the present invention is that the displacement of the piston by the wedge shaped member is not determined by the distance the wedge shaped member travels along its linear direction of travel so long as the first position of the wedge shaped member allows the piston to at least contact a portion of the first planar surface and the second position of the wedge shaped member allows the piston to contact at least a portion of the second planar surface. It will be apparent to those skilled in the art that the shape of the wedge shaped member can be incorporated into other embodiments of the mechanical driver according to the present invention. The above configuration is explained in relation to the mechanical driver wherein the piston is in contact with the wedge shaped member. It will be clear that it can be applied in a similar way in the mechanical driver wherein a lever is in contact with the wedge shaped member.

In a further embodiment of any of the above mechanical drivers according to the invention, The lever comprises one end that forms the fixed rotation point and a moveable end that is moveable about the fixed rotation point. The movable end of the lever is arranged so that it is in permanent contact with the wedge shaped member, and that the wedge shaped member is able to slide relative to the movable end of the lever. There is provided a point on the lever, at a distance along the lever between the fixed point of rotation of the lever and the point of contact of the lever with the wedge shaped member, where the lever is in permanent contact with a piston. The piston is arranged such that it can move in a linear direction that is as close as practically possible along a tangent to the angular movement of the lever. When the wedge shaped member moves from the first position to the second position it acts to deflect the moveable end of the

5

lever from a first position to a second position. When the lever is deflected to its second position by the wedge shaped member, the lever deflects the piston from a first position to a second position. When the shape memory alloy cools, a return spring can pull the wedge shape member from its second position to its first position, the lever rotates from its second position to its first position, and the piston moves from its second position to its first position. The mechanical driver allows for the accuracy and repeatability of movement of the piston from its first position to its second position to be optimised by accurately defining the wedge shaped member and also by optimising the position of the piston along the lever relative to the fixed point of rotation of the lever and the contact point between the lever and the wedge shaped member. The position on the lever that provides the point of contact with the piston relative to the position of the fixed point of rotation and the contact point between the lever and the wedge shaped member can be optimised to deliver the piston movement and accuracy required.

Current manufacturing technologies such as injection molding of polymer parts can produce plastic parts within a manufacturing tolerance of about ± 20 microns. In some cases, ± 10 microns is possible. It is therefore possible using current injection molding techniques to define the wedge shaped member of this invention to those accuracies. In certain circumstances this provides sufficient piston movement accuracy that is suitable for manufacturing micro-pumps that can be used in drug delivery device capable of accurate drug delivery.

In a further embodiment of any of the above mechanical drivers according to the invention, the wedge shaped member can have two angled surfaces. One surface is coupled to the piston or the lever and the other is coupled to an angled surface at a fixed position. The two angled surfaces of the wedge shaped member are positioned such that they are essentially opposite each other. It will be apparent to those skilled in the art that this arrangement of angled surfaces allows the gradient of the surfaces to be reduced while retaining the deflection caused by the movement of the wedge shaped member.

In a further embodiment of any of the above mechanical drivers according to the invention, the wedge shaped member is arranged so that it cannot rotate about its axis of travel or perpendicular to its axis of travel. This arrangement increases the efficiency of the deflection caused by the wedge shaped member when it moves between its first and second positions.

In a further embodiment of any of the above mechanical drivers according to the invention, the position of the piston can be arranged at a point along the lever to increase the accuracy of the micro-pump. Positioning the piston on the lever at a point between the contact point between the wedge shaped member and the lever, and the fixed point of rotation of the lever allows the accuracy of the movement of the piston to be optimised.

In a further embodiment of any of the above mechanical drivers according to the invention, the piston is arranged so that as far as is possible its direction of travel is restricted. This arrangement increases the efficiency of the deflection caused by the wedge shaped member or the lever acting on the piston.

In a further embodiment of any of the above mechanical drivers according to the invention, the lever is sufficiently rigid to avoid bending of the lever during the action of the miniature mechanical driver.

6

In a further embodiment of any of the above mechanical drivers according to the invention, a spring is incorporated to move the lever from its second position to its first position. The spring may be a silicone structure connected to the lever at one end and to a fixed point at the other.

In a further embodiment of any of the above mechanical drivers according to the invention, a spring is incorporated to move the piston from its second position to its first position. The spring may be a silicone structure connected to the piston at one end and to a fixed point at the other.

In a further embodiment of any of the above mechanical drivers according to the invention, the mechanical driver is used to drive the reciprocating piston of a micro-pump for infusing liquid drugs. The pump can comprise a pumping chamber having an inlet and outlet, wherein the volume of the pumping chamber is caused to change by the action of the mechanical driver. Such a pump can be part of a drug delivery device comprising a reservoir of drug maintained at a positive pressure such that when the pumping chamber is filling with liquid drug, the positive pressure of the drug reservoir assists in the filling of the pumping chamber. To prevent unintentional delivery of liquid drug from the drug reservoir, valves are provided at the inlet and outlet to the pumping chamber. The valves can be designed such that the inlet valve allows fluid to enter the pumping chamber from the drug reservoir when the pumping chamber is filling, and the outlet valve only allows fluid to pass through it when the volume of the pumping chamber is reduced by the action of the miniaturised mechanical driver.

In a further embodiment of any of the above mechanical drivers according to the invention, the mechanical driver is formed from parts that are essentially flat and that can be easily stacked together to form the miniaturised mechanical driver. This preferred embodiment of the present invention has the advantage of being relatively simple to manufacture.

In a further embodiment of any of the above mechanical drivers according to the invention, the return springs for the wedge shaped member and the lever are formed from an elastomeric material such as silicone, and formed during the fabrication of the wedge shaped member or the lever.

In a further embodiment of any of the above mechanical drivers according to the invention, the mechanical driver is suitable for a micro-pump with a pumping chamber with a volume of less than 100 micro liters.

INTRODUCTION TO DRAWINGS

The above objects and other advantages of the present invention will become more apparent by describing in detail the preferred embodiments of the present invention with reference to the attached drawings in which:

FIG. 1 is a cross section through a mechanical driver according to a first embodiment of the invention.

FIG. 2 is a cross section through a mechanical driver according to a first embodiment of the invention showing the shape memory alloy wire contracted and the piston deflected to its second position.

FIG. 3 shows the orientation of the wedge shaped member, shape memory alloy and return spring

FIG. 4 is a cross section through a mechanical driver according to a second embodiment of the invention

FIG. 5 is a cross section through a mechanical driver according to a second embodiment of the invention showing the shape memory alloy wire contracted and the piston deflected to its second position.

FIG. 6 is a cross section through a mechanical driver according to a third embodiment of the invention

FIG. 7 is a cross section through a mechanical driver according to a third embodiment of the invention showing the shape memory alloy wire contracted and the piston deflected to its second position.

FIG. 8 is a cross section through a mechanical driver according to a fourth embodiment of the invention

FIG. 9 is a cross section through a mechanical driver according to a fourth embodiment of the invention showing the shape memory alloy wire contracted and the piston deflected to its second position.

FIG. 10 is a plan view of a first embodiment of the wedge shaped member, the shape memory alloy and the return spring of a mechanical driver according to the present invention.

FIG. 11 is a plan view of a second embodiment of the wedge shaped member, the shape memory alloy and the return spring of a mechanical driver according to the present invention.

FIG. 12 is a plan view of a third embodiment of the wedge shaped member, the shape memory alloy and the return spring of a mechanical driver according to the present invention.

FIG. 13 is a plan view of a fourth embodiment of the wedge shaped member, the shape memory alloy and the return spring of a mechanical driver according to the present invention.

FIG. 14 is a plan view of a first embodiment of the lever and lever return springs of a mechanical driver according to the present invention.

FIG. 15 is a plan view of a second embodiment of the lever and lever return springs of a mechanical driver according to the present invention.

FIG. 16 is a cross section through a first arrangement of the return spring on the piston

FIG. 17 is a cross section through a second arrangement of the return spring on the piston

FIG. 18 is a cross section through a third arrangement of the return spring on the piston

FIG. 19 is a cross section through a fourth arrangement of the return spring on the piston

FIG. 20 is a cross section through a mechanical driver according to a fifth embodiment of the invention

FIG. 21 is a cross section through a mechanical driver according to a fifth embodiment of the invention showing the shape memory alloy wire contracted and the piston deflected to its second position.

FIG. 22 is a cross section view of a micro pump comprising a mechanical driver according to the present invention.

DETAILED DESCRIPTION

The first embodiment of the mechanical driver is shown in FIG. 1. The mechanical driver is a miniature mechanical driver. FIG. 1 shows the miniaturised mechanical driver 10 in its non activated state. The miniaturised mechanical driver 10 comprises a wedge shaped member 102. The wedge shaped member 102 is arranged so that it can move in one plane and in an essentially linear direction. The wedge shaped member 102 has at least one angled surface arranged so that it forms an angle with the direction of travel of the wedge shaped member 102. A shape memory actuator 103 is fixed to the wedge shaped member 102 at one end and to the frame 105 of the miniaturised mechanical driver 10. The shape memory actuator 103 is arranged so that it acts along the linear direction of travel of the wedge shaped member 102. The shape memory actuator 103 is also referred to as

shape memory alloy. Both terms relate to an actuator made from a shape memory alloy material. A return spring 104 is attached at one end to the wedge shaped member 102 and to the frame 105 of the miniaturised mechanical driver 10 at the other end. The return spring 104 is arranged so that it acts along the linear direction of travel of the wedge shaped member 102. A piston 101 is arranged so that it is in constant contact with the angled surface of the wedge shaped member 102 at one end. The piston 101 is further arranged so that it can move in a direction that is essentially perpendicular to the plane in which the wedge shaped member 102 is arranged to move. FIG. 1 shows the device in the start position with the wedge shaped member 102 and the piston 101 being at their first position (also referred to as their start position), the shape memory alloy 103 in a cooled state and elongated and the return spring 104 contracted.

The shape memory alloy 103 can be in the form of wire formed from a number of shape memory effect metal alloys such as NiTi (Nickel-Titanium), CuZnAl, and CuAlNi. The shape memory alloy can be fixed to the frame 105 and the wedge shaped member 102 using techniques such as crimping or other techniques known to those skilled in the art. In a preferred embodiment the return spring 104 is formed from an elastomeric material such as silicone or rubber. In a preferred embodiment the return spring 104 is formed by injection molding or casting the elastomeric material. In a further preferred embodiment the return spring 104 is formed by casting the elastomeric material and then curing the material with radiation. In a further preferred embodiment the elastomeric material is injection molded or cast in situ and to fix the return spring 104 to the wedge shaped member 102 and to the frame 105. A number of elastomeric materials are suitable for this purpose including self adhesive liquid silicone preparations for injection molding such as Elastosil LR 3071 and Silpuran 6700 (Wacker Chemie AG, München, Germany) and self adhesive liquid silicone preparations for casting and ultra violet light curing such as Loctite Nuva-Sil Silicone (Henkel AG & Co. KGaA, Dusseldorf, Germany) and Novaguard RTV 800-305 (Novaguard, Cleveland, Ohio, USA). It is preferred that the material used in the fabrication of the frame 105 is the same as the material chosen for the wedge shaped member 102. This would simplify the manufacturing process and could allow the manufacture of the wedge shaped member 102 and the frame 105 in a single process such as an injection molding step.

FIG. 2 shows the mechanical driver described in FIG. 1 when the mechanical driver has been operated. Operation of the mechanical driver 20 requires that the shape memory alloy 203 is heated, preferably by passing an electric current through it. The shape memory alloy 203 contracts when heated and acts to displace the wedge shaped member 202 to its second position. Displacement of the wedge shaped member 202 acts to elongate the return spring 204. Displacement of the wedge shaped member 202 to its second position also acts to displace the piston 201 to its second position and in a linear direction essentially perpendicular to the plane of movement of the wedge shaped member 202. FIG. 2 shows the shaped memory alloy 203 in a contracted state, the wedge shaped member 202 in its second position, the return spring 205 in an elongated state and the piston 201 displaced to its second position.

When the shape memory alloy 203 is allowed to cool or is actively cooled, the shape memory alloy 203 extends. When the shape memory alloy 203 is allowed to cool, the return spring 204 acts to return the wedge shaped member 202 to the first position. When the wedge shaped member

202 returns to its first position the piston 201 returns to its first position. The first positions (also referred to as the start positions) of the wedge shaped member 202 and the piston 201 are the positions shown in FIG. 1 of the wedge shaped member 102 and the piston 101.

FIG. 3 shows a preferred embodiment of the wedge shaped member 301 and the frame 302 of a miniaturised mechanical driver 30 according to this invention. A shape memory alloy 303 is fixed to the wedge shaped member 301 at one end and to the frame 302 at the other end. A return spring 304 is fixed to the wedge shaped member 301 at one end and to the frame 302 at the other end. The wedge shaped member 301 is arranged so that it moves in a linear fashion along the x axis of the miniaturised mechanical driver 30. The wedge shaped member 301 is also preferably arranged so that the angled surface of the wedge shaped member 304 can move along axis x while maintaining a fixed angle with axis z and axis x. In a preferred embodiment the wedge shaped member 301 is arranged so that it cannot rotate about axis x or axis y.

FIG. 4 shows a second embodiment of the mechanical driver according to the present invention substantially identical to the first embodiment of the mechanical driver according to the present invention described with reference to FIGS. 1 and 2 and incorporating a wedge shaped member as described with reference to FIG. 3 except that a lever 404 is included to operatively connect the wedge shaped member 402 to the piston 401. The lever 404 is rotatable at a fixed rotation point. The wedge shaped member 402 is operatively coupled to and in constant contact with the lever 404 at a point at a distance from the fixed rotation point to deflect the lever 404 about the fixed rotation point. A piston drive point is located on and in constant contact with the lever 404, at a distance from the fixed rotation point of the lever 404. The piston 401 is in constant contact with the lever 404 at the piston drive point. It will be appreciated by those skilled in the art that elements of the first embodiment and of the wedge shaped member described with reference to FIG. 3 can be combined in the second embodiment. FIG. 4 shows the second embodiment of the mechanical driver 40 according to the present invention in the start position. The wedge shaped member 402, the lever 404 and the piston 401 are in the first position. The shape memory alloy 403 is elongated and the return spring 405 compressed. The lever 404 is arranged such that it is in constant contact with the wedge shaped member 402. The wedge shaped member 402 is connected to the frame 406 via the return spring 405. The fixed rotation point is also referred to as pivot point. Both terms relate to the fixed point about which the lever 404 in use rotates.

FIG. 5 shows the activated form of the second embodiment of the mechanical driver according to the present invention. The shape memory alloy 503 is heated preferably by passing an electric current through it. The heated shape memory alloy 503 contracts and moves the wedge shaped member 502 from its first position shown in FIG. 4 to its second position shown in FIG. 5. When the wedge shaped member 502 moves from its first position to its second position it elongates the return spring 505. When the wedge shaped member 502 moves from its first position to its second position it also moves the lever 504 from its first position shown in FIG. 4 to its second position shown in FIG. 5. The lever moves in an angular direction about the pivot point 507. When the lever 504 moves to its second position it moves the piston 501 from its first position shown in FIG. 4 to its second position shown in FIG. 5. In the mechanical driver 50, the lever 504 is connected to the frame

at the fixed rotation point 507. The piston drive point is also referred to as contact point. Both terms relate to the point on the lever 504 by which the piston 501 is driven to move.

FIG. 6 shows a third embodiment of the mechanical driver according to the present invention that is substantially similar to the second embodiment described in FIGS. 4 and 5 except for the location of the contact point 606 (also referred to as piston drive point) between the piston 601 and the lever 604. The piston 601 is arranged at a point between the pivot point 607 of the lever 604 and the end of the lever in contact with the wedge shaped member 602. The location of the contact point 606 can be fixed relative to the pivot point 607 and the contact point of the lever with the wedge shaped member 602 to optimise the accuracy of the movement of the piston 601. By way of example, an error in moving the lever at the contact point with the wedge shaped member 602 can be reduced by fixing the contact point 606 closer to the pivot point 607. FIG. 6 shows the third embodiment of the mechanical driver 60 according to the present invention in the start position with the wedge shaped member 602, the lever 604 and the piston 601 being at their first position, the shape memory alloy 603 in a cooled state and elongated and the return spring 605 contracted.

Those skilled in the art will appreciate that elements of the wedge shaped member design described in FIG. 3 can be incorporated into the third embodiment of the present invention. Those skilled in the art will also appreciate that elements of the design of the lever described in FIGS. 14 and 15 can also be incorporated into the third embodiment of the mechanical driver according to the present invention.

FIG. 7 shows the third embodiment of the mechanical driver according to the present invention in an activated state. Activation of the third embodiment of the mechanical driver according to the present invention is substantially similar to the activation of the second embodiment of the mechanical driver according to the present invention. The wedge shaped member 702, the lever 704 and the piston 701 of the mechanical driver 70 are located in their second position. FIG. 7 furthermore shows the shape memory alloy 703, the return spring 705 and the piston drive point 706.

FIG. 8 shows a fourth embodiment of the mechanical driver according to the present invention that is substantially similar to the second and third embodiments of the mechanical driver according to the present invention with the exception of the wedge shaped member 802. The wedge shaped member 802 in the fourth embodiment of the mechanical driver according to the present invention has two angled surfaces. The first angled surface is in contact with the lever 804 and the second angled surface is arranged on the opposing surface of the wedge shaped member 804 to the first angled surface. The second angled surface of the wedge shaped member 802 is in contact with the frame 807. The area of the frame 807 that is in contact with the wedge shaped member 802 is also angled to accommodate the angled surface of the wedge shaped member 802. The angled surface of the frame 807 is also arranged such that when the wedge shaped member 802 is moved from its first position to its second position the angled surface of the frame 807 deflects the wedge shaped member towards the lever 804. The activated state of the fourth embodiment of the mechanical driver according to the present invention is described in greater detail in FIG. 9. It will be apparent to those skilled in the art that certain aspects of the wedge shaped member described in FIG. 3 can be incorporated in to the fourth embodiment of the mechanical driver according to the present invention. FIG. 8 shows the fourth embodiment of the mechanical driver according to the present

11

invention in the start position. The wedge shaped member **802**, the lever **804** and the piston **801** are in the first position. The shape memory alloy **803** is elongated and the return spring **805** compressed. The lever **804** is arranged such that it is in constant contact with the wedge shaped member **802**. FIG. **8** furthermore shows the piston drive point **806** of the lever **804** of the mechanical driver **80**. FIG. **9** shows the activated state of the fourth embodiment of the mechanical driver according to the present invention. The shape memory alloy **903** is heated preferably by passing an electric current through it. The heated shape memory alloy **903** contracts and moves the wedge shaped member **902** from its first position shown in FIG. **8** to its second position shown in FIG. **9**. When the wedge shaped member **902** moves from its first position to its second position it elongates the return spring **905**. When the wedge shaped member **902** moves from its first position to its second position it moves along the angled surface of the frame **907** such that the angled surface of the frame **907** and the angled surface of the wedge shaped member **902** act cooperatively to displace the wedge shaped member **902** towards the lever **904**.

When the wedge shaped member **902** moves from its first position to its second position it moves the lever **904** from its first position shown in FIG. **8** to its second position shown in FIG. **9**. When the lever **904** moves to its second position it moves the piston **901** from its first position shown in FIG. **8** to its second position shown in FIG. **9**. FIG. **9** furthermore shows the piston **901** and the piston drive point **906** of the lever **904** of the mechanical driver **90**. The fourth embodiment of the mechanical driver according to the present invention has the advantage of increasing the distance the wedge shaped member is able to displace the lever and the piston for a given length of contraction by the shaped memory alloy without an increase in the angle of the angled surface.

It will be appreciated by those skilled in the art that the wedge shaped member and the frame described in the fourth embodiment of the mechanical driver according to the present invention can be incorporated into the first and second embodiments of the mechanical driver according to the present invention.

FIGS. **10**, **11**, **12** and **13** show alternative arrangements of the wedge shaped member and the shape memory alloy and the return spring. FIG. **10** shows an arrangement of the shape memory alloy **1001** fixed at one end to the wedge shaped member **1002** at first fixing point **1004** and to the frame **1006** at second fixing point **1005**. FIG. **10** shows an arrangement of the wedge shaped member and the return spring **1003**. The return spring **1003** is arranged so that one end is fixed to the frame and the other is fixed to the end of the wedge shaped member **1002** that is opposite to the shape memory alloy fixing point **1004**. FIG. **11** shows an alternative arrangement for the shape memory alloy **1101** that is substantially similar to the arrangement shown in FIG. **10** except for the arrangement of the shape memory alloy **1101**. The shape memory alloy **1101** is fixed at the first fixing point **1104** to the frame **1108** and at a second fixing point **1105** to the frame **1108**. The shape memory alloy **1101** is passed around two members **1106** and **1107** positioned on the wedge shaped member **1102** such that it is free to slide around these members. This arrangement is advantageous in that the electrical connections to the shape memory alloy **1101** can also serve as the fixing points **1104** and **1105**. The wedge shaped member **1102** is connected to the frame **1108** via the return spring **1103**. FIG. **12** shows an alternative arrangement substantially similar to that shown in FIG. **11** with the addition of a connecting bridge comprising flexible

12

tether members **1208** and **1209** between the wedge shaped member **1202** and the frame **1210**. The members **1208** and **1209** are arranged to allow the wedge shaped member **1202** to at least move along its intended plane of movement. The members **1208** and **1209** are advantageous by allowing the wedge shaped member and the frame to be moulded as a single unit. The memory shape alloy **1201** is passed around two members **1206** and **1207** and fixed at the first and second fixing points **1204**, **1205**. The wedge shaped member **1202** is connected to the frame **1210** via the return spring **1203**. Those skilled in the art will appreciate that the features can be combined with the arrangement shown in FIG. **10**. FIG. **13** shows an alternative arrangement of the wedge shaped member and the return spring. The return spring **1307** and **1308** is fixed at one end to the frame **1309** and at the other end to a side of the wedge shaped member **1302** other than the side that is opposite to the fixing point of the shape memory alloy **1301**. The memory shape alloy **1301** is passed around two members **1306** and **1307** and fixed at the first and second fixing points **1303**, **1304**. Those skilled in the art will appreciate that certain elements of the arrangement shown in FIG. **13** can be incorporated into the arrangement shown in FIG. **10**. It will also be apparent to those skilled in the art that the features described in the arrangement shown in FIG. **12** can be incorporated into the arrangement described in FIG. **13**.

The shape memory alloy can be fixed at the fixing points using crimping, soldering or welding. Those skilled in the art will appreciate that other methods exist for fixing the shape memory alloy.

It will be apparent to those skilled in the art that certain aspects of the arrangements shown in FIGS. **10**, **11**, **12** and **13** can be incorporated into other embodiments of the present invention.

FIGS. **14** and **15** show the addition of a return spring to the lever described in FIGS. **4** and **5**. The return spring acts to return the lever to its initial position and to keep the movable end of the lever in constant contact with the wedge shaped member. In FIG. **14** the return spring **1402** is formed such that one end is connected to the lever **1401** and the other end is connected to the frame **1404**. FIG. **14** shows the return spring **1402** fixed to the end of the lever **1401** able to rotate about the pivot point **1403**.

FIG. **15** shows an alternative embodiment of the return spring for the lever. The return spring **1502** and **1503** is attached at one end to the side of the lever **1501** and at the other end to the frame **1505**. It will be apparent to those skilled in the art that there are other suitable arrangements for the return spring. The lever **1501** is rotatable about the pivot point **1054**.

In preferred embodiment the return spring **1402**, **1502** and **1503** is formed from an elastomeric material such as silicone or rubber. In a preferred embodiment the return spring **1402**, **1502** and **1503** is formed by injection molding or casting the elastomeric material. In a further preferred embodiment the return spring **1402**, **1502** and **1503** is formed by casting the elastomeric material and then curing the material with radiation. In a further preferred embodiment the elastomeric material is injection molded or cast in situ and to fix the return spring **1402**, **1502** and **1503** to the lever **1401** and **1501** and to the frame **1404** and **1505**. A number of elastomeric materials are suitable for this purpose including self adhesive liquid silicone preparations for injection molding such as Elastosil LR 3071 and Silpuran 6700 (Wacker Chemie AG, München, Germany) and self adhesive liquid silicone preparations for casting and ultra violet light curing such as Loctite Nuva-Sil Silicone (Henkel AG & Co. KGaA,

Dusseldorf, Germany) and Novaguard RTV 800-305 (Novaguard, Cleveland, Ohio, USA). It is preferred that the material used in the fabrication of the frame **105** is the same as the material chosen for the wedge shaped member **102**. This would simplify the manufacturing process and could allow the manufacture of the wedge shaped member **102** and the frame **105** in a single process such as an injection molding step.

The lever **1401** and **1501** is made from a polymer that provides the appropriate mechanical properties and resists wear from the movement of the wedge shaped member and the piston. It is preferred that the material also has a low coefficient of friction. Materials such as polyether ether ketone (PEEK), Grivory and polycarbonate and polyacrylate are all suitable materials for the lever **1401** and **1501**. Those skilled in the art will recognise other appropriate materials for the lever **1401** and **1501**. The lever **1401** and **1501** can be fabricated using polymer injection molding or polymer casting techniques. Other methods for fabricating the lever **1401** and **1501** are known to those skilled in the art. It is preferred that the fabrication technique used for forming the lever **1401** and **1501** can produce parts with an accuracy of better than ± 20 microns. It is also preferred that the techniques chosen to fabricate the lever **1401** and **1501** can produce large numbers of parts, quickly and cost effectively. It is preferred that the material used in the fabrication of the frame **1404** and **1505** is the same as the material chosen for the lever **1401** and **1501**. This would simplify the manufacturing process and could allow the manufacture of the lever **1401** and **1501** and the frame **1404** and **1505** in a single process such as an injection molding step.

In FIG. **14** and FIG. **15** there is described a lever **1401** and **1501** respectively where one end of the lever is fixed to the frame **1404** and **1505** respectively by a pivot point **1404** and **1504** respectively. In a preferred embodiment the pivot point **1404** and **1504** can be formed by removing material from the lever **1401** and **1501** in this part of the device to allow the lever to bend and for the bending to be essentially restricted to the pivot point **1404** and **1504**. It will be appreciated by those skilled in the art that alternative pivot point structures can be used.

It will be appreciated by those skilled in the art that the embodiments of the lever shown in FIGS. **14** and **15** can be incorporated into other embodiments of the mechanical driver according to the present invention.

FIGS. **16**, **17**, **18** and **19** show alternative arrangements for a return spring for the piston. The return spring acts to return the piston to its initial position (its first position) and to hold the piston in constant contact with the lever or the wedge shaped member in the embodiments of the present invention. FIG. **16** shows a return spring **1603** formed between the perimeter of an opening in the frame **1602** and the perimeter of the piston **1601**. FIG. **17** shows a return spring **1703** formed between the perimeter of an opening in the frame **1702** and the surface and perimeter of the piston **1601**. FIG. **18** shows a return spring **1803** formed on one face of the frame **1802** and the perimeter of the piston **1801**. FIG. **19** shows a return spring **1903** formed on one face of the frame **190** and the surface and perimeter of the piston **1901**.

In preferred embodiment the return spring for the piston **1601**, **1701**, **1801** and **1901** is formed from an elastomeric material such as silicone or rubber. In a preferred embodiment the return spring for the piston **1601**, **1701**, **1801** and **1901** is formed by injection molding or casting the elastomeric material. In a further preferred embodiment the return spring for the piston **1601**, **1701**, **1801** and **1901** is formed

by casting the elastomeric material and then curing the material with radiation. In a further preferred embodiment the elastomeric material is injection molded or cast in situ and to fix the return spring for the piston **1601**, **1701**, **1801** and **1901** to the piston **1601**, **1701**, **1801** and **1901** and to the frame **1602**, **1702**, **1802** and **1902**. A number of elastomeric materials are suitable for this purpose including self adhesive liquid silicone preparations for injection molding such as Elastosil LR 3071 and Silpuran 6700 (Wacker Chemie AG, München, Germany) and self adhesive liquid silicone preparations for casting and ultra violet light curing such as Loctite Nuva-Sil Silicone (Henkel AG & Co. KGaA, Dusseldorf, Germany) and Novaguard RTV 800-305 (Novaguard, Cleveland, Ohio, USA). It is preferred that the material used in the fabrication of the frame **1602**, **1702**, **1802** and **1902** is the same as the material chosen for the piston **1601**, **1701**, **1801** and **1901**. This would simplify the manufacturing process and could allow the manufacture of the piston **1601**, **1701**, **1801** and **1901** and the frame **1602**, **1702**, **1802** and **1902** in a single process such as an injection molding step.

It will be apparent to those skilled in the art that the arrangements for a return spring for the piston described in FIGS. **16**, **17**, **18** and **19** can be incorporated in to other embodiments of the mechanical driver according to the present invention, such as the described first, second, third, fourth and fifth embodiments of the mechanical driver.

In a preferred embodiment the return spring for the piston can form the pumping membrane of a micro pump.

FIG. **20** describes a fifth embodiment of the mechanical driver according to the present invention. The elements of the fifth embodiment of the mechanical driver according to the present invention are essentially similar to the element described in the third embodiment of the mechanical driver according to the present invention in FIG. **6**. The elements of the fifth embodiment of the mechanical driver according to the present invention are arranged so that when in the inactive state the return springs **2004**, **2007** and **2005** are placed under tension when the device is assembled. Tensioning of the return spring **2004** ensures that the piston **2001** is constantly in contact with the lever **2004** and ensures that any movement in the lever **2004** moves the piston **2001**. This increases the accuracy and repeatability of the action of the mechanical driver. Tensioning of the return spring **2007** ensures that the lever **2004** is constantly in contact with the angled surface of the wedge shaped member **2002** and ensures that movement of the wedge shaped member **2002** moves the lever **2004**. This further increases the accuracy and repeatability of the action of the mechanical driver. Tensioning of the return spring **2005** ensures that the shape memory alloy **2003** is held in tension and ensures that the contraction of the shape memory alloy **2003** moves the shape memory alloy **2003**. This further increases the accuracy and repeatability of the action of the device. FIG. **20** shows the fifth embodiment of the present invention in the start position. The wedge shaped member **2002**, the lever **2004** and the piston **2001** are in the first position. The shape memory alloy **2003** is elongated and the return springs **2004**, **2005** and **2007** are at their respective first tension points. Furthermore, the frame **2006** of the mechanical driver **200** is shown.

FIG. **21** shows the fifth embodiment of the mechanical driver according to the present invention in an activated state and is similar to the activated state described with reference to the third embodiment of the mechanical driver according to the present invention. The piston **2101**, the return springs **2104**, **2105**, **2107**, the wedge shaped member **2102**, the

15

shape memory alloy **2103**, the lever **2104**, and the frame **2106** of the mechanical driver **210** are shown.

An example of the application of the miniaturised mechanical driver according to the mechanical driver according to the present invention is as a micro-pump as shown in FIG. **22**. The micro-pump **220** has a pumping chamber **2207** with fluidic connection via an inlet valve **2208** to a reservoir **2211**. At least part of the pumping chamber wall is flexible, and in a preferred embodiment the piston **2204** of the miniature mechanical driver is fixed to the flexible portion of the pumping chamber wall. In a preferred embodiment the flexible portion of the pumping chamber **2207** wall forms the return spring for the piston **2204** as described with reference to FIGS. **16**, **17**, **18** and **19**. Heating of the shape memory alloy **2202** causes the shape memory alloy **2202** to contract and displace the wedge shaped member **2201** from its first position to its second position. This causes the return spring **2205** on the wedge shaped member **2201** to be stretched from its first position to its second position. The movement of the wedge shaped member **2201** also displaces the lever **2203** from its first position to its second position and the lever **2203** displaces the piston **2204** from its first position to its second position. The lever **2203** is connected to the frame via a return spring **2212** and rotated about the fixed rotation point **2206**. The movement of the piston **2204** from its first position to its second position causes the volume of the pumping chamber **2207** to decrease and forces the fluid out of the pumping chamber **2207** through outlet valve **2209**. Allowing the shape memory alloy **2202** to cool causes the shape memory alloy **2202** to elongate to its starting length assisted by the contraction of the return spring **2205** on the wedge shaped member **2205** to its starting length. Movement of the wedges shaped member **2201** to its first position allows the lever **2203** to be returned to its first position by the action of the return spring **2212** on the lever **2203**. The return of the lever **2203** to its first position allows the piston to be returned to its first position by the action of the return spring on the piston. The return of the piston **2204** to its first position increases the volume of the pumping chamber **2207** and allows fluid to enter the pumping chamber **2207** from the reservoir **2211** via the inlet valve **2208**.

The inlet valve **2208** and outlet valve **2209** are one-way valves. The outlet valve **2209** opens when the pressure in the pumping chamber **2207** increases when the piston **2204** is moved from its first position to its second position and the volume of the pumping chamber **2207** decreases. The inlet valve **2208** closes when the pressure in the pumping chamber increases. When the pumping chamber is filled with fluid, fluid is selectively forced through the outlet valve when the piston moves for its first position to its second position. The inlet valve opens when the pressure in the pumping chamber **2207** decreases as the piston **2204** returns from its second position to its first position and the volume of the pumping chamber **2207** increases. The outlet valve **2209** closes when the pressure in the pumping chamber decreases. Therefore, fluid is selectively drawn from the reservoir **2211** into the pumping chamber **2207** when the piston moves to its second position from its first position. Repeated operation of the of the micro-pump **220** causes fluid to be pumped from the reservoir **2211** to the outlet **2210**. To assist the drawing of fluid from the reservoir **2211**, the reservoir **2211** may be pressurised.

The micro-pump described with reference to FIG. **22** finds particular use in an infusion system for the infusion of therapeutic products.

16

The following clauses are offered as a further description of the mechanical driver, pump and infusion system according to the invention.

Clause 1

A miniature mechanical driver comprising:

a piston,

a wedge shaped member operatively coupled and in constant contact with the piston, and able to deflect the piston, and

a shape memory alloy operatively coupled to the wedge shaped member and able to move the wedge shaped member such that the wedge shaped member deflects the piston, the shape memory alloy is held at a predetermined tension in its start position.

Clause 2

A mechanical driver comprising:

a lever, able to rotate at a fixed point,

a wedge shaped member operatively coupled to and in constant contact with the lever at a point some distance from the fixed rotation point, and able to deflect the lever about the fixed rotation point,

a shape memory alloy operatively coupled to the wedge shaped member and able to move the wedge shaped member such that the wedge shaped member deflects the lever, the shape memory alloy is held at a predetermined tension in its start position, and

a piston drive point located on and in constant contact with the lever, some distance from the fixed rotation point of the lever.

Clause 3

Mechanical driver according to clause 1 or 2, wherein the wedge shaped member has a single angled surface operatively coupled to the piston or the lever.

Clause 4

Mechanical driver according to clause 1 or 2, wherein the wedge shaped member has two angled surfaces operatively coupled to the piston or the lever.

Clause 5

Mechanical driver according to clause 3 or 4, wherein the wedge shaped member has surfaces at either end of each angled surface that are essentially planar to the direction of travel of the wedge shaped member and that are in contact with the piston or the lever when the wedge shaped member is in its first and second positions respectively.

Clause 6

Mechanical driver according to any of the preceding clauses, wherein the wedge shaped member is attached to a frame by flexible tethers.

Clause 7

Mechanical driver according to any of the preceding clauses, wherein the shape memory alloy is a wire.

Clause 8

Mechanical driver according to clause 7, wherein the shape memory wire is fixed at one end to the wedge shaped member.

Clause 9

Mechanical driver according to clause 7 or 8, wherein the shape memory wire is looped around at least part of the wedge shaped member and the ends of the shape memory wire are attached to fixed points.

Clause 10

Mechanical driver according to any of the clauses 2-9, wherein the piston drive point is located relative to the fixed rotation point of the lever and the coupling point of the wedge shaped member with the lever so as to optimise the accuracy of movement of the piston.

17

Clause 11

Mechanical driver according to any of the preceding clauses, further comprising a return spring operatively coupled to the wedge shaped member, and acting against the force of the shape memory alloy.

Clause 12

Mechanical driver according to clause 11, wherein the return spring is an elastomeric material.

Clause 13

Mechanical driver according to clause 11 or 12, wherein the return spring is fabricated using an injection molding or casting technique.

Clause 14

Mechanical driver according to any of the preceding clauses, further comprising a return spring operatively coupled to the piston, and acting to return the piston to its starting position.

Clause 15

Mechanical driver according to clause 14, wherein the return spring on the piston is biased when the piston is in its starting position.

Clause 16

Mechanical driver according to clause 14 or 15, wherein the return spring forms the pumping membrane of a micro pump.

Clause 17

Mechanical driver according to any of the clauses 14-16, wherein the return spring is an elastomeric material.

Clause 18

Mechanical driver according to clause 17, wherein the return spring is fabricated using an injection molding or casting technique.

Clause 19

Mechanical driver according to any of the preceding clauses, further comprising a return spring operatively coupled to the lever, and acting to return the lever to its starting position.

Clause 20

Mechanical driver according to clause 19, wherein the return spring on the lever is biased when the lever is in its starting position.

Clause 21

Mechanical driver according to clause 19 or 20, wherein the return spring is an elastomeric material.

Clause 22

Mechanical driver according to clause 21, wherein the return spring is fabricated using an injection molding or casting technique.

Clause 23

A pump comprising the miniature mechanical driver according to any preceding clause.

Clause 24

Pump according to clause 23 for pumping liquid therapeutic product comprising a pumping chamber having an inlet valve and an outlet valve wherein a volume of the pumping chamber is caused to change by actuation of the miniature mechanical driver.

Clause 25

An infusion system including the pump of any of clauses 23 and 24. It will be apparent to those skilled in the art that various modifications of the present invention are envisaged without departing from the scope of the invention, which is defined by the appending claims.

18

The invention claimed is:

1. A mechanical driver comprising:

a piston;

a wedge shaped member operatively coupled and in constant contact with the piston and moveable relative to the piston; and

a shape memory alloy operatively coupled to the wedge shaped member to move the wedge shaped member relative to the piston such that the wedge shaped member deflects the piston;

wherein the shape memory alloy is held at a predetermined tension in its start position; and

wherein the wedge shaped member is arranged so that it moves only in a substantially linear direction relative to the piston while the wedge shaped member is operatively coupled and in constant contact with the piston.

2. The mechanical driver according to claim 1, wherein the wedge shaped member has a single angled surface.

3. The mechanical driver according to claim 2, wherein the angled surface is an inclined straight surface.

4. The mechanical driver according to claim 1, wherein the wedge shaped member has two angled surfaces.

5. The mechanical driver according to claim 4, wherein the angled surfaces are two opposite inclined straight surfaces.

6. The mechanical driver according to claim 2,

wherein the single angled surface has a first end and a second end;

wherein the wedge shaped member has a first flat surface and a second flat surface; and

wherein the first flat surface is adjacent to the first end and the second flat surface is adjacent to the second end, and the first and second flat surfaces are essentially planar to the direction of travel of the wedge shaped member.

7. The mechanical driver according to claim 6, wherein the wedge shaped member is movable from the start position into a second position, and vice versa, and the piston is in contact with the first flat surface when the wedge shaped member is in the start position and the piston is in contact with the second flat surface when the wedge shaped member is in the second position.

8. The mechanical driver according to claim 1, wherein the wedge shaped member is attached to a frame by flexible tethers.

9. The mechanical driver according to claim 1, wherein the shape memory alloy is a wire.

10. The mechanical driver according to claim 9, wherein the shape memory wire is fixed at one end to the wedge shaped member.

11. The mechanical driver according to claim 9, wherein the shape memory wire is looped around at least part of the wedge shaped member and ends of the shape memory wire are attached to fixed points.

12. The mechanical driver according to claim 1, wherein the mechanical driver further comprises a return spring operatively coupled to the wedge shaped member, and acting against a force of the shape memory alloy.

13. The mechanical driver according to claim 12, wherein the return spring is an elastomeric material.

14. The mechanical driver according to claim 12, wherein the return spring is fabricated using an injection molding or casting technique.

15. The mechanical driver according to claim 1, wherein the mechanical driver further comprises a return spring operatively coupled to the piston, and acting to return the piston to its starting position.

16. The mechanical driver according to claim 15, wherein the return spring is biased when the piston is in its starting position.
17. The mechanical driver according to claim 15, wherein the return spring is an elastomeric material. 5
18. The mechanical driver according to claim 17, wherein the return spring is fabricated using an injection molding or casting technique.
19. A pump comprising the mechanical driver according to claim 1. 10
20. The pump according to claim 19 for pumping a liquid therapeutic product comprising a pumping chamber having an inlet valve and an outlet valve, wherein a volume of the pumping chamber is caused to change by actuation of the mechanical driver. 15
21. An infusion system including the pump according to claim 19.
22. A mechanical driver comprising:
- a piston;
 - a wedge shaped member operatively coupled and in 20 constant contact with the piston and moveable relative to the piston;
 - a shape memory alloy operatively coupled to the wedge shaped member to move the wedge shaped member relative to the piston such that the wedge shaped 25 member deflects the piston, wherein the shape memory alloy is held at a predetermined tension in its start position; and
 - a return spring operatively coupled to the piston, and acting to return the piston to its starting position; 30
- wherein the return spring forms a pumping membrane of a micro pump.

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